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Otsuki et al.

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(54) **TRANSLATION/ROTATION ERROR
COMPENSATION AMOUNT CREATING
DEVICE**

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patent is extended or adjusted under 35
U.S.C. 154(b) by 382 days.

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Oct. 2, 2012 (JP) 2012-220675

(57) **ABSTRACT**

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G05B 15/00 (2006.01)
G05B 19/404 (2006.01)

A translation/rotation error compensation amount creating device creates, for a multi-axis machining apparatus having two rotation axes, a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes. The translation/rotation error compensation amount creating device calculates the translation error compensation amount and the rotation error compensation amount based on an assembly error (set value) including at least an assembly error in a table surface or an assembly error in a spindle turning centerline in a multi-axis machining apparatus as well as the positions of the two rotation axes, and inputs the calculated error compensation amounts to a numerical controller controlling the multi-axis machining apparatus.

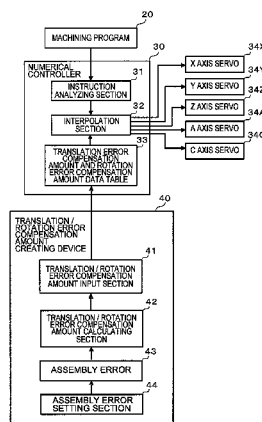
(52) **U.S. Cl.**
CPC ... **G05B 19/404** (2013.01); **G05B 2219/49189**
(2013.01); **G05B 2219/49198** (2013.01)

(58) **Field of Classification Search**
CPC G05B 19/404; G05B 2219/49189;
G05B 2219/49198

USPC 700/275

See application file for complete search history.

2 Claims, 12 Drawing Sheets



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FIG. 1

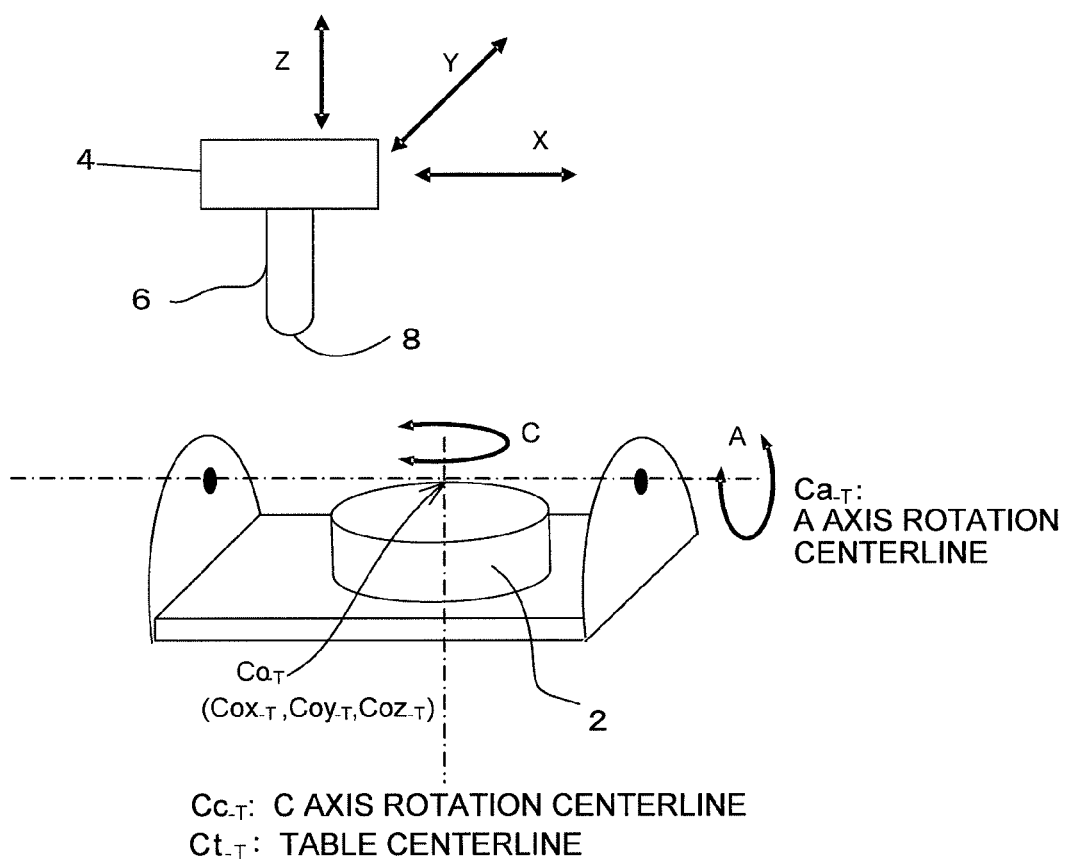


FIG. 2

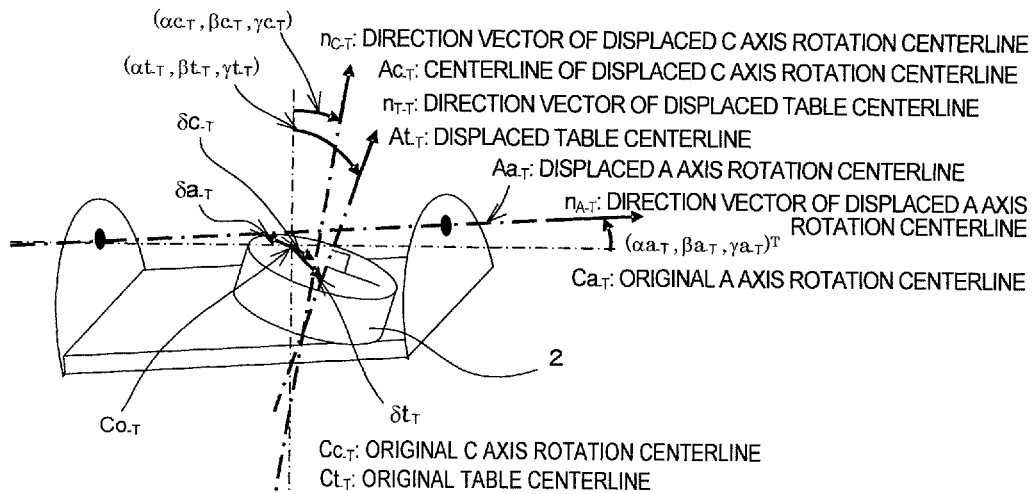


FIG. 3

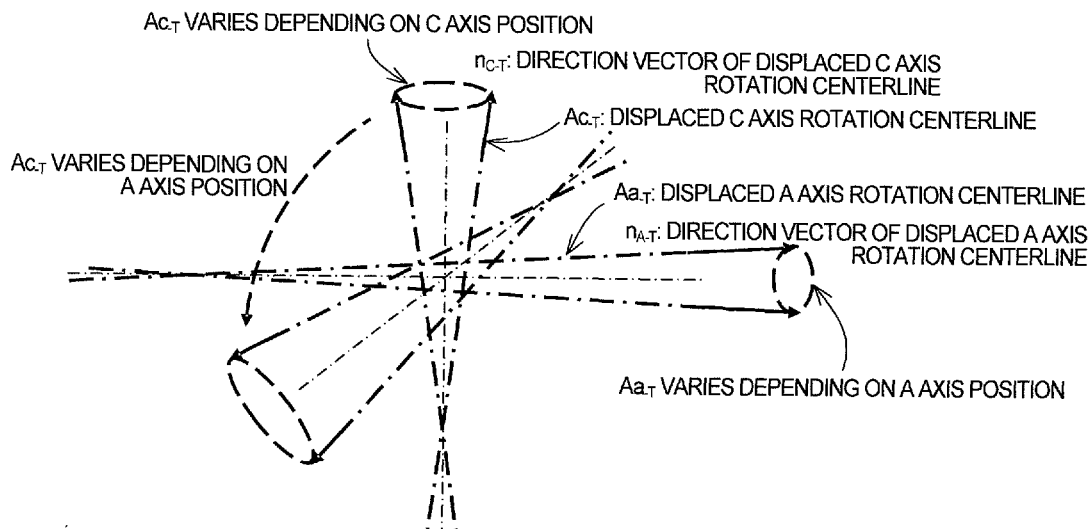


FIG. 4

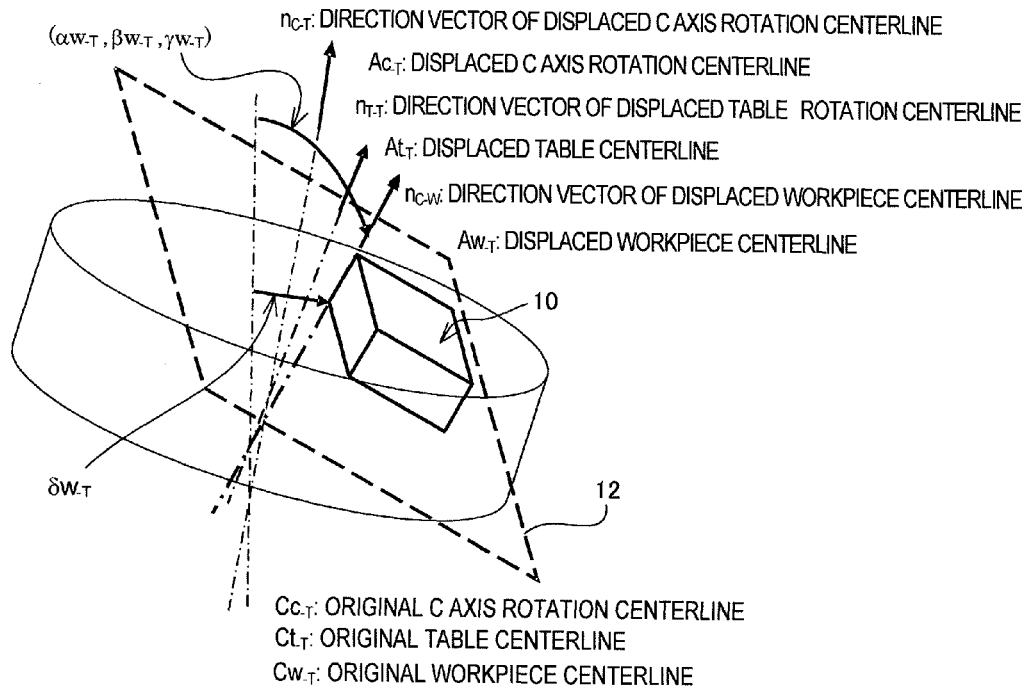


FIG. 5

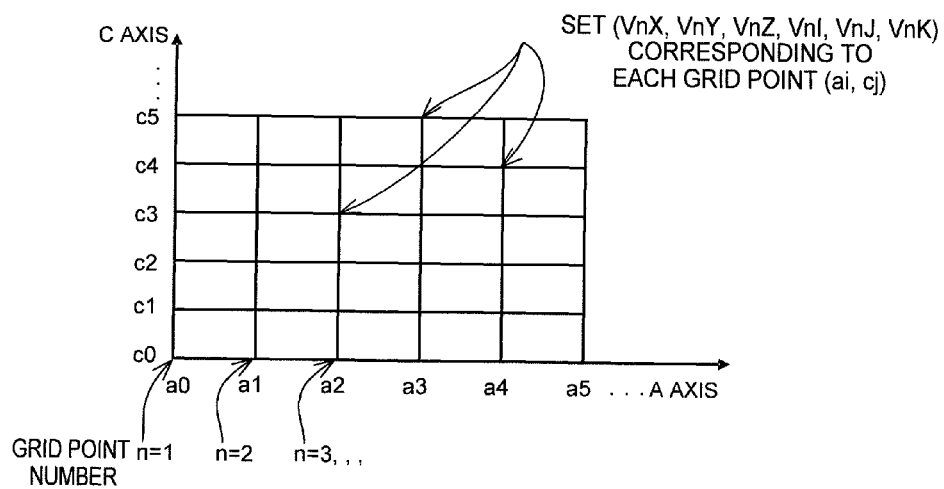


FIG. 6

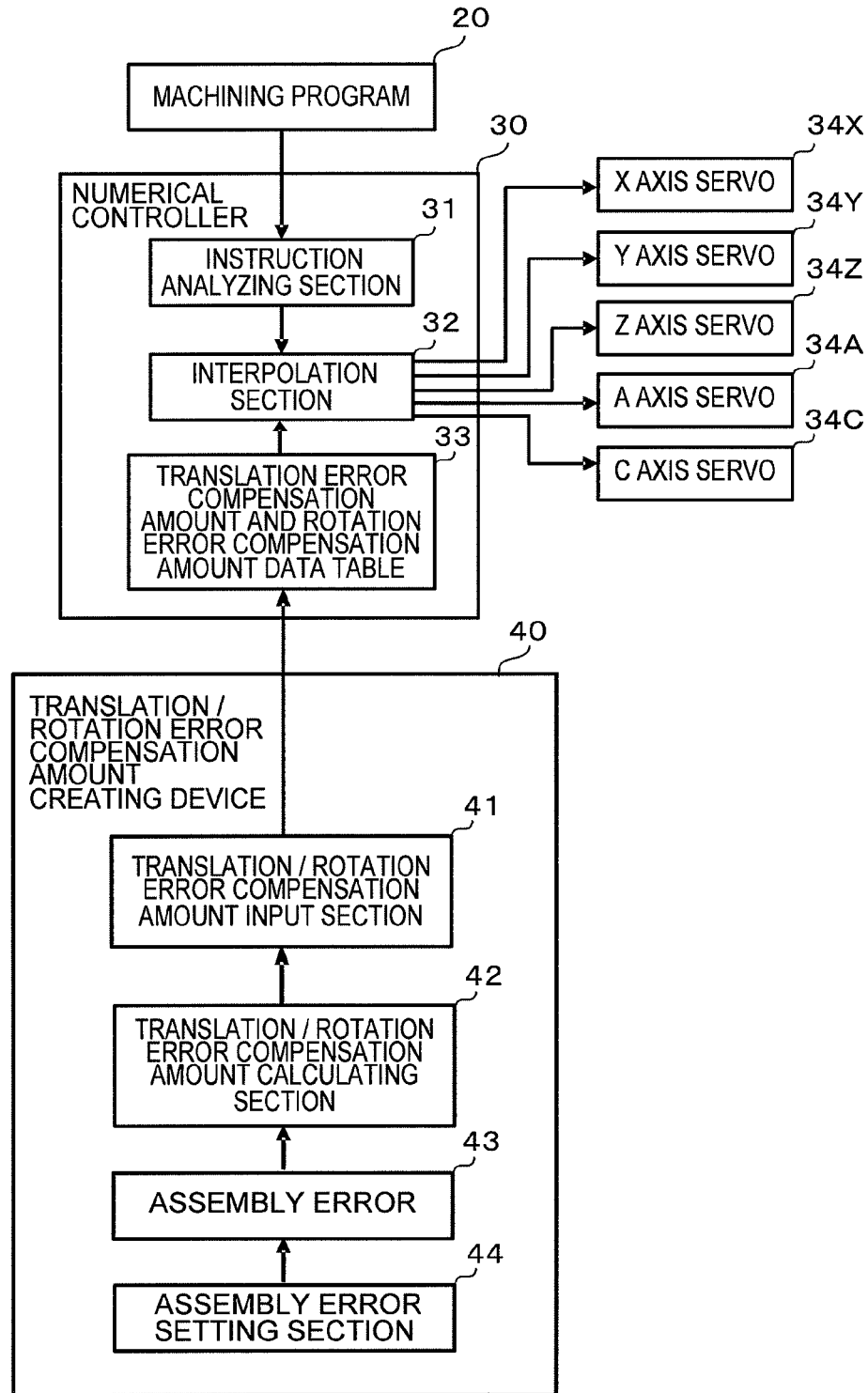


FIG. 7

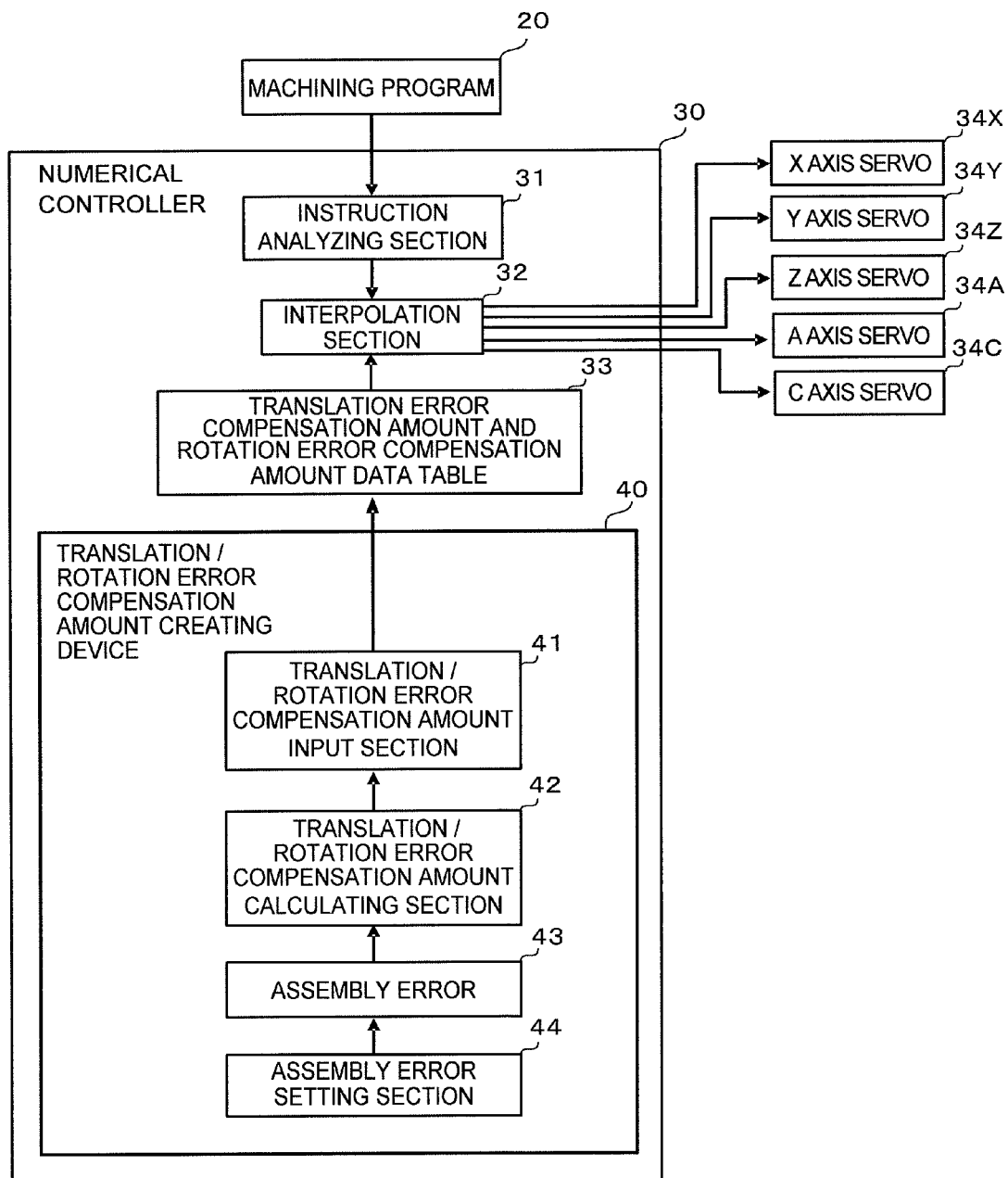


FIG. 8

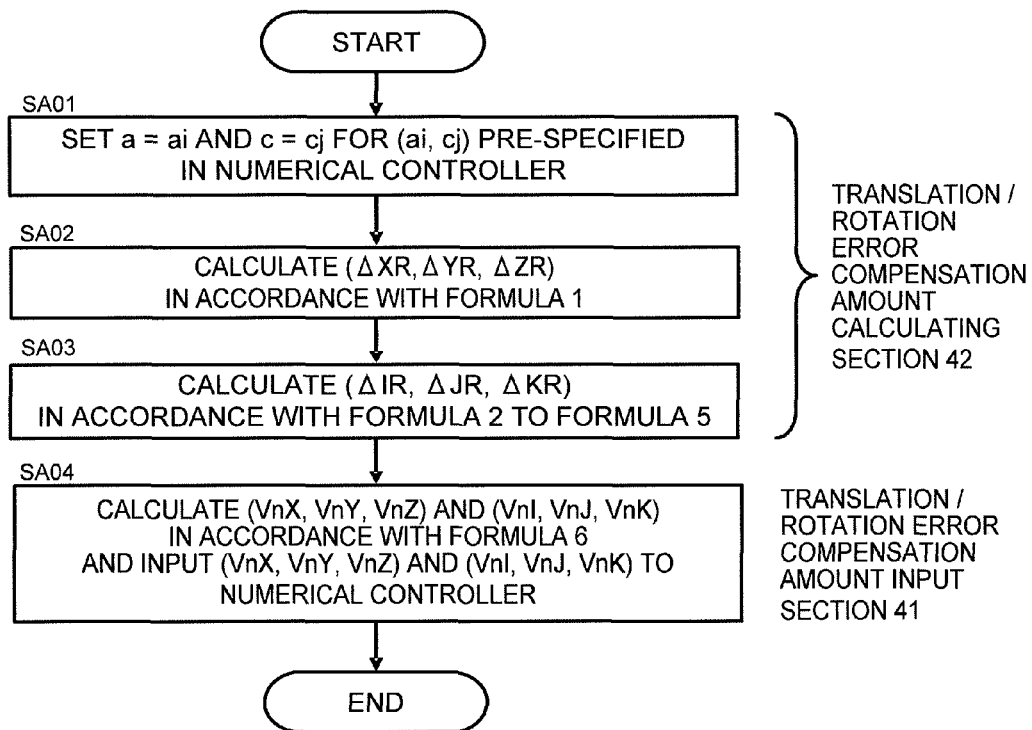


FIG. 9

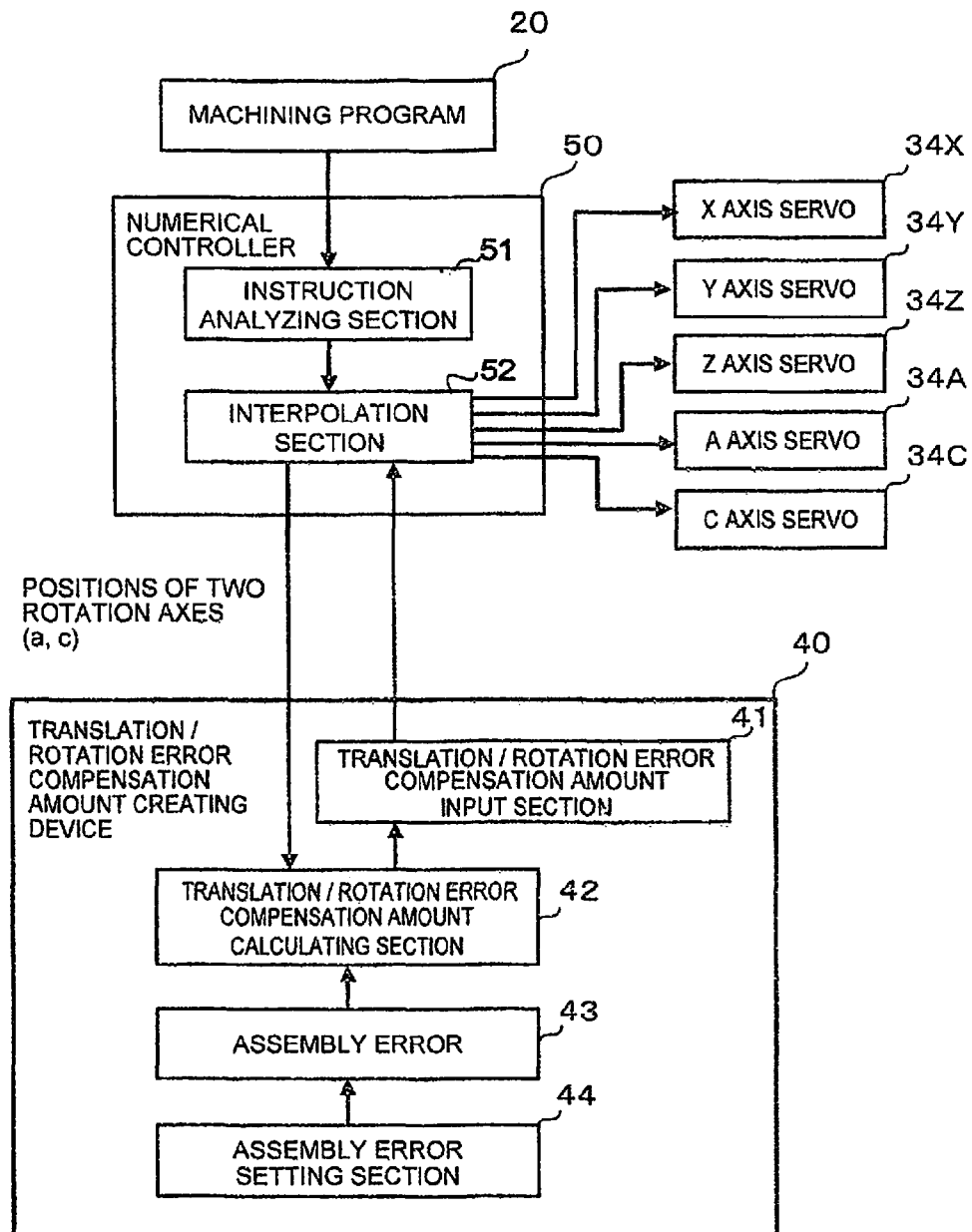


FIG. 10

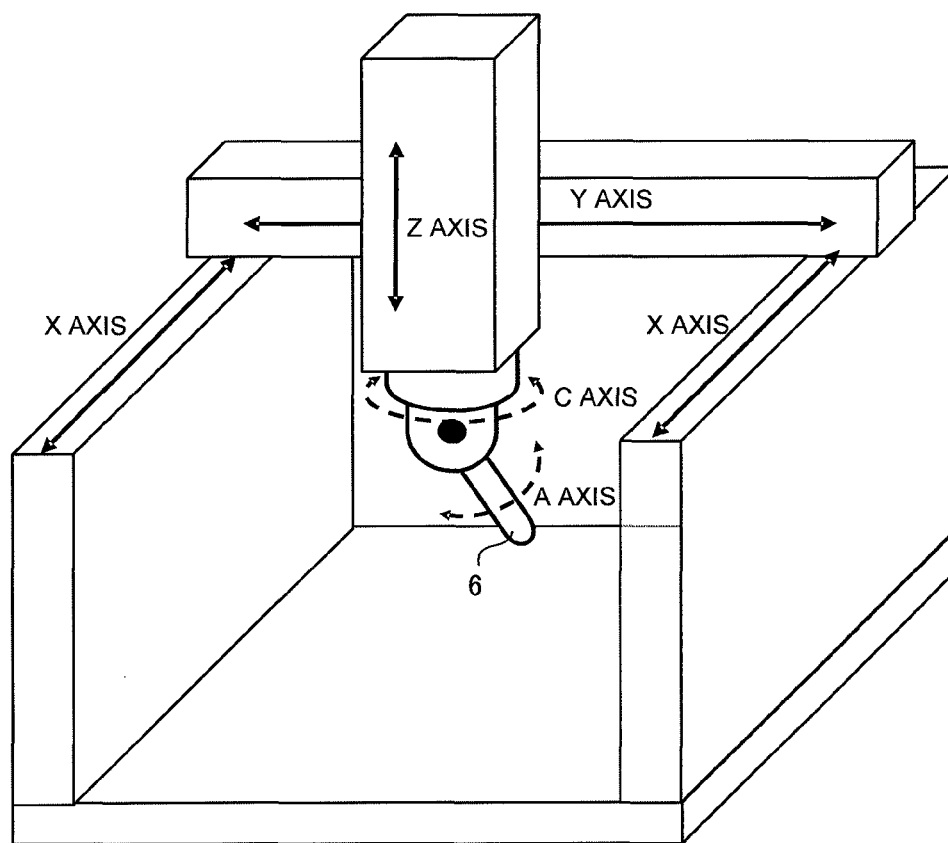


FIG. 11

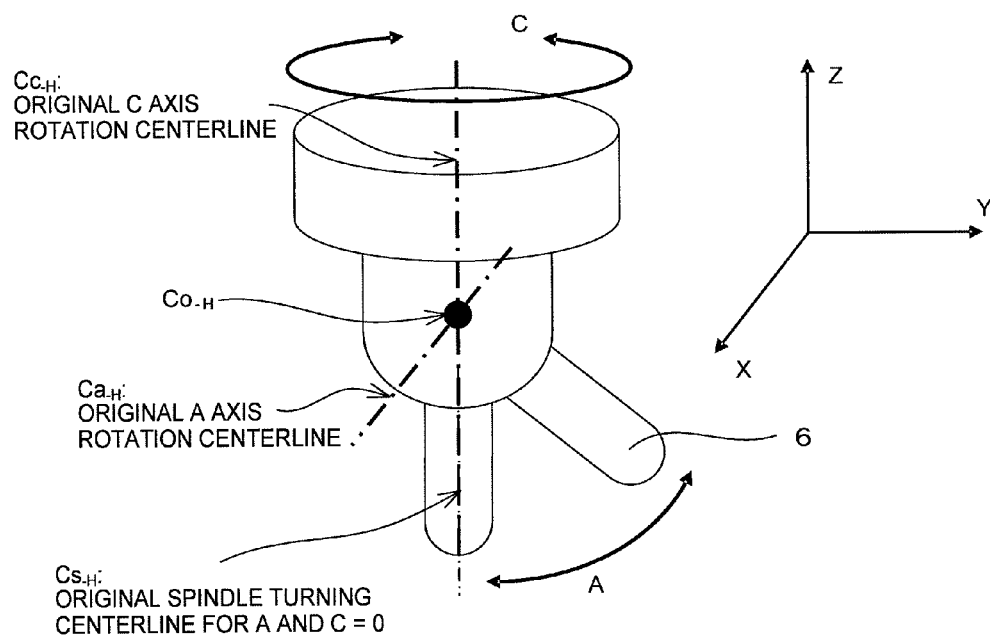


FIG. 12

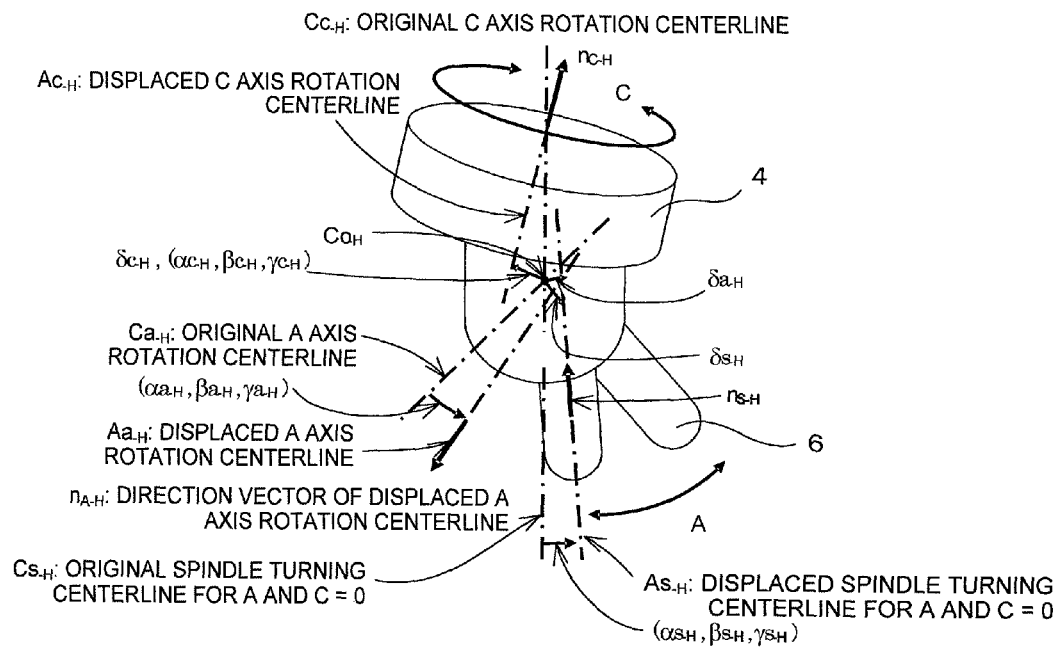


FIG. 13

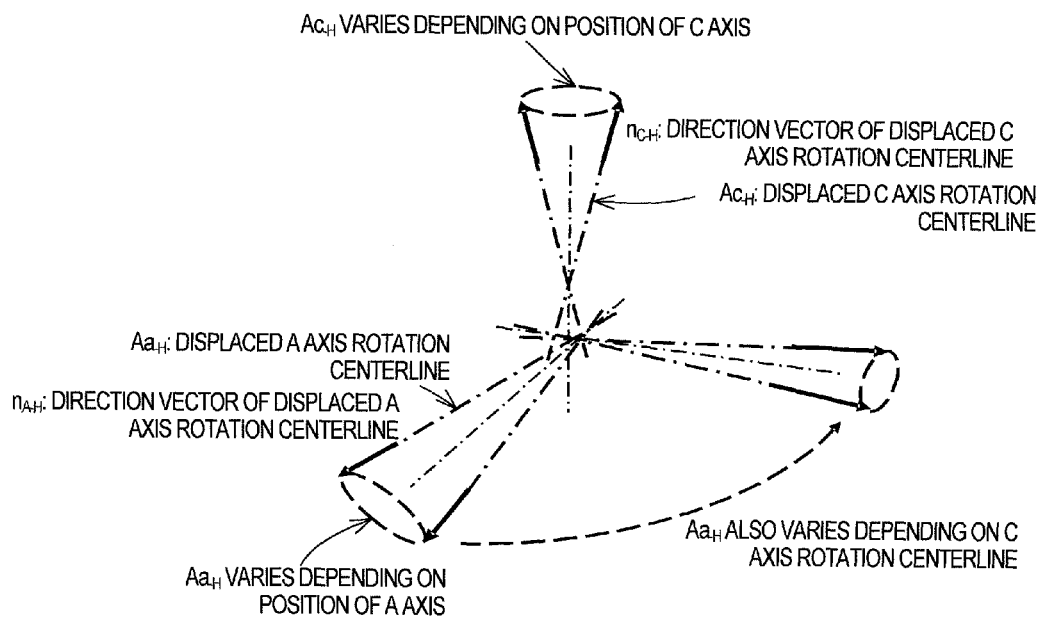


FIG. 14

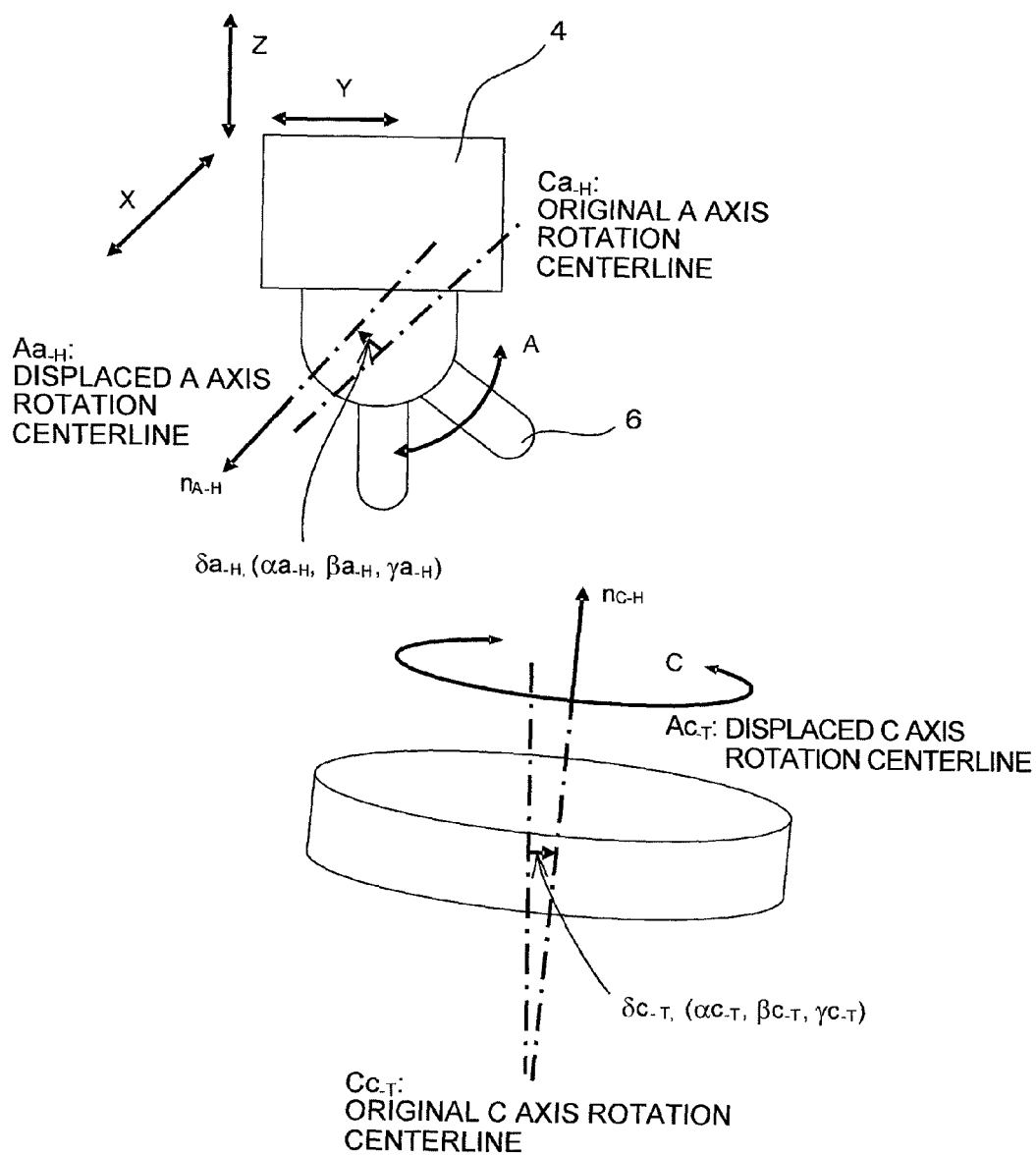
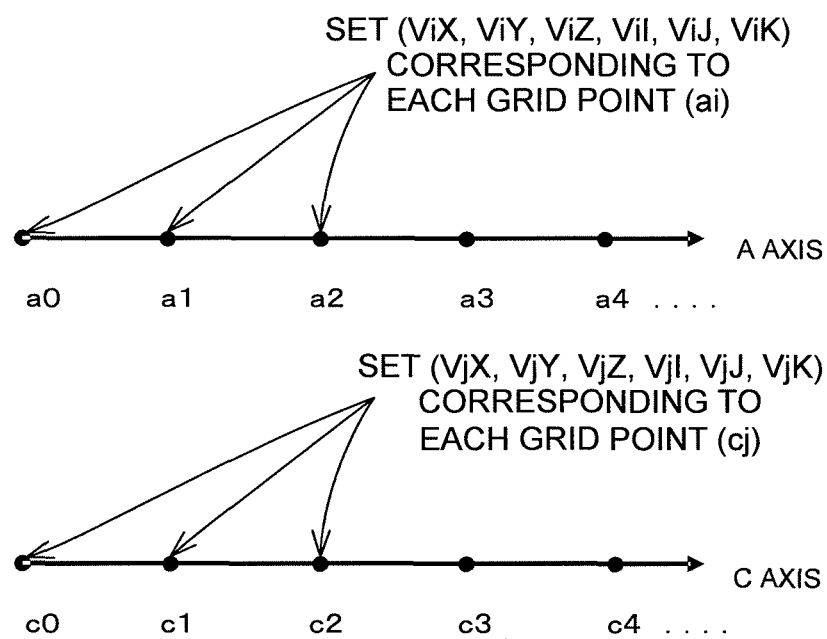


FIG. 15



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TRANSLATION/ROTATION ERROR COMPENSATION AMOUNT CREATING DEVICE

RELATED APPLICATIONS

The present application is based on Japanese Application Number 2012-220675, filed Oct. 1, 2012, the disclosure of which is hereby incorporated by reference herein in its entirety.

BACKGROUND OF THE INVENTION

1. Field of the Invention

The present invention relates to a device that creates a translation error compensation amount and a rotation error compensation amount both depending on a rotation axis, based on a preset assembly error and a rotation axis position in order to compensate an assembly error in a multi-axis machining apparatus having at least two rotation axes.

Now, the translation error compensation amount and rotation error compensation amount depending on the rotation axis will be described.

In "JIS B6190-7 FIG. 1 b) Error motion of rotation axis" of Japanese Industrial Standard, errors depending on a C shaft are represented as:

"EXC: radial motion in an X direction",
"EYC: radial motion in a Y direction",
"EYC: axial motion",
"EAC: tilting motion around an X shaft",
"EBC: tilting motion around an Y shaft", and
"ECC: angular positioning error".

According to the present invention, of the errors depending on a C shaft, "EXC: radial motion in the X direction", "EYC: radial motion in the Y direction", and "EYC: axial motion" are referred to as translation errors (specifically, translation errors depending on the C shaft). "EAC: tilting motion around the X shaft", "EBC: tilting motion around the Y shaft", and "ECC: angular positioning error" are referred to as rotation errors (specifically, rotation errors depending on the C axis).

For another rotation axis, for example, an A axis, the following are present: "EXA: axial motion", "EYA: radial motion in the Y direction", "EZA: radial motion in a Z direction axial motion", "EAA: angular positioning error", "EBA: tilting motion around the Y shaft", and "ECA: tilting motion around a Z shaft".

Thus, the translation errors and the rotation errors varying depending on the positions of the rotation axes are hereinafter referred to as translation errors and rotation errors depending on the rotation axes, and compensation amounts by which those errors are compensated are hereinafter referred to as translation error compensation amounts and rotation error compensation amounts depending on the rotation axes.

2. Description of the Related Art

Japanese Patent Application Laid-open No. 2004-272887 (JP 2004-272887 A) discloses a technique for compensating an assembly error in a rotation axis in a multi-axis machining apparatus having rotation axes. The technique uses many matrix operations using trigonometric functions. Thus, the technique can be partly carried out in practice, but a numerical controller that needs to perform high-speed control takes a long time for arithmetic operations, and the technique is thus difficult to carry out in practice. Moreover, the technique disadvantageously fails to take into account an assembly error in a table surface, that is, an error between a table

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surface centerline and a table rotation axis rotation centerline, more specifically, an error in which the table surface fails to be perpendicular to the table rotation axis (C axis described below) rotation centerline and in which the table surface centerline deviates from the table rotation axis (C axis) rotation centerline.

On the other hand, Japanese Patent Application Laid-open No. 2009-151756 (JP 2009-151756 A) discloses a technique for compensating an error based on a translation error compensation amount and a rotation error compensation amount both depending on rotation axes. The technique performs matrix operations but does not take such a long time as needed for the technique described in JP 2004-272887 A. Thus, the technique disclosed in JP 2009-151756 A allows a numerical controller to perform compensation in practice. However, to determine the compensation amount, the technique divides a two-dimensional coordinate system for two rotation axes into pieces like a grid, sets a translation error compensation amount and a rotation error compensation amount at each of the resultant grid points, and calculates a compensation amount for the position of the rotation axis based on compensation amounts for grid points enclosing the position of the rotation axis. That is, the technique is not a method for obtaining the compensation amount from the assembly error. Thus, when an attempt is made to compensate the assembly error by the technique disclosed in JP 2009-151756 A, the assembly error needs to be converted into a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes and to set the translation error compensation amount and the rotation error compensation amount. However, JP 2009-151756 A fails to disclose such a conversion technique.

Furthermore, Journal of Technical Disclosure No. 2009-505137 discloses a technique for creating the compensation amount disclosed in JP 2009-151756 A from the assembly error in a multi-axis machining apparatus (table rotating multi-axis machining apparatus) having two rotation axes for rotation of a table which is disclosed in JP 2004-272887 A. The technique fails to take an assembly error in the table surface into account. Journal of Technical Disclosure No. 2009-505137 describes a technique for creating a compensation amount from an assembly error in a rotation axis in a table rotating 5-axis machining apparatus and further states that the technique can be applied to a head rotating 5-axis machining apparatus (see FIG. 10) in which a head rotates based on two rotation axes and a mixed 5-axis machining apparatus (see FIG. 14) in which both a head and a table rotate.

However, the inventors have found that it is insufficient to apply the technique disclosed in Journal of Technical Disclosure No. 2009-505137 directly to the tool head rotating 5-axis machining apparatus or the mixed 5-axis machining apparatus. The reason is as follows.

In terms of an error in a member installed on a rotor, the assembly error in the tool head rotating multi-axis machining apparatus corresponding to the assembly error in the table surface in the table rotating multi-axis machining apparatus is an assembly error in a spindle turning centerline, that is, an error in which the spindle turning centerline fails to be orthogonal to the rotational centerline of a tool head tilting axis (an A axis described below). JP 2004-272887 A takes the assembly error in the spindle turning centerline into account while Journal of Technical Disclosure No. 2009-505137 does not take into account the assembly error in the table surface in the table rotating multi-axis machining apparatus as described above. Thus, even when

the technique disclosed in Journal of Technical Disclosure No. 2009-505137 is applied to the tool head rotating multi-axis machining apparatus disclosed in JP 2004-272887 A, the assembly error in the spindle turning centerline fails to be compensated. This also applies to the mixed multi-axis machining apparatus.

SUMMARY OF THE INVENTION

Thus, an object of the present invention is to provide a translation/rotation error compensation amount creating device for a numerical controller controlling a multi-axis machining apparatus having at least two rotation axes by:

converting an assembly error including an assembly error in a table surface in a table rotating multi-axis machining apparatus having a rotary table into a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes;

converting an assembly error including an assembly error in a spindle turning centerline in a tool head rotating multi-axis machining apparatus into a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes; or

converting an assembly error including an assembly error in a table surface and an assembly error in a spindle turning centerline in a mixed multi-axis machining apparatus into a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes,

wherein the translation/rotation error compensation amount creating device enables the numerical controller to compensate the assembly error in the table surface or the assembly error in the spindle turning centerline in practice in a shorter time.

A translation/rotation error compensation amount creating device according to the present invention creates, for a multi-axis machining apparatus having at least two rotation axes, a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes. The translation/rotation error compensation amount creating device includes an assembly error setting section that presets an assembly error including at least an assembly error in a table surface or an assembly error in a spindle turning centerline in the multi-axis machining apparatus, a translation/rotation error compensation amount calculating section that calculates the translation error compensation amount and the rotation error compensation amount based on the assembly error set by the assembly error setting section and positions of the two rotation axes, and a translation/rotation error compensation amount input section that inputs the calculated translation error compensation amount and rotation error compensation amount to a numerical controller controlling the multi-axis machining apparatus.

The positions of the two rotation axes may be the positions of the two rotation axes obtained from the numerical controller at every interpolation period.

The two rotation axes are two rotation axes for table rotation, the multi-axis machining apparatus is a table rotating multi-axis machining apparatus, and the assembly error is the assembly error in the table surface and an assembly error in the two rotation axes for table rotation.

The two rotation axes are two rotation axes for tool head rotation, the multi-axis machining apparatus is a tool head rotating multi-axis machining apparatus, and the assembly error is the assembly error in the spindle turning centerline and an assembly error in the two rotation axes for tool head rotation.

The two rotation axes are one rotation axis for table rotation and one rotation axis for tool head rotation, the multi-axis machining apparatus is a mixed multi-axis machining apparatus with one rotation axis for table rotation and one rotation axis for tool head rotation, and the assembly error is the assembly error in the table surface, an assembly error in the one rotation axis for table rotation, an assembly error in the one rotation axis for tool head rotation, and the assembly error in the spindle turning centerline.

The numerical controller according to the present invention controls a multi-axis machining apparatus having at least two rotation axes, and has a numerical control section that analyzes a machining program to carry out interpolation and a translation/rotation error compensation amount creating device that creates a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes. Furthermore, the translation/rotation error compensation amount creating device has an assembly error setting section that presets an assembly error including at least an assembly error in a table surface or an assembly error in a spindle turning centerline in the multi-axis machining apparatus, a translation/rotation error compensation amount calculating section that calculates the translation error compensation amount and the rotation error compensation amount based on the assembly error set by the assembly error setting section and positions of the two rotation axes, and a translation/rotation error compensation amount input section that inputs the calculated translation error compensation amount and rotation error compensation amount to the numerical controller.

The positions of the two rotation axes may be the positions of the two rotation axes obtained from the numerical controller at every interpolation period.

The present invention can provide the translation/rotation error compensation amount creating device for the numerical controller controlling the multi-axis machining apparatus having at least two rotation axes by:

converting the assembly error including the assembly error in the table surface in the table rotating multi-axis machining apparatus having the rotary table into the translation error compensation amount and rotation error compensation amount depending on the rotation axes;

converting the assembly error including the assembly error in the spindle turning centerline in the tool head rotating multi-axis machining apparatus into the translation error compensation amount and rotation error compensation amount depending on the rotation axes; or

converting the assembly error including the assembly error in the table surface and the assembly error in the spindle turning centerline in the mixed multi-axis machining apparatus into the translation error compensation amount and rotation error compensation amount depending on the rotation axes, wherein the translation/rotation error compensation amount creating device enables the numerical controller to compensate the assembly error in the table surface or the assembly error in the spindle turning centerline in practice in a shorter time.

A calculation for the conversion is much more complicated than a calculation described in Journal of Technical Disclosure No. 2009-505137 in which an assembly error not including an assembly error in a table surface in a table rotating multi-axis machining apparatus is converted into a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes, as described below in an embodiment.

In accordance with notation in JP 2009-151756 A, the translation error compensation amount depending on the

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rotation axes is denoted by (ΔXR , ΔYR , ΔZR), and the rotation error compensation amount depending on the rotation axes is denoted by (ΔIR , ΔJR , ΔKR).

The term "compensation" as used herein refers to correct a linear-axis machine coordinate position so that a relative positional relation between a table and a tool center point in an original instruction is the same as the relative relation between the actual table (with an assembly error) and the compensated tool center point position.

The specification is intended for the conversion of an assembly error in the table surface, that is, an assembly error including a translation error and a rotation error in the table surface (table centerline described below) with respect to a table rotation axis rotation centerline, into a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes. However, an installation error (a translation error and a rotation error in a workpiece centerline described below) during workpiece installation may be considered to be an assembly error (translation error and rotation error) in the table surface. Thus, the present invention is applicable to an error during workpiece installation.

BRIEF DESCRIPTION OF THE DRAWINGS

The above-described and other objects and features of the present invention will be apparent from the description below of embodiments given with reference to the attached drawings, in which:

FIG. 1 is a diagram illustrating a table rotating multi-axis machining apparatus (5-axis machining apparatus) without any assembly error;

FIG. 2 is a diagram illustrating that an assembly error including an assembly error in a table surface is represented as an error in a rotation axis rotation centerline (A axis rotation centerline and C axis rotation centerline) and an error (translation error and rotation error) in the table surface with respect to a table rotation axis rotation centerline (C axis rotation centerline);

FIG. 3 is a diagram showing how the displaced rotation axis rotation centerline varies, focusing only on the rotation axis rotation centerline;

FIG. 4 is a diagram illustrating that a workpiece is installed on a displaced workpiece installation surface on the displaced table in FIG. 2;

FIG. 5 is a diagram illustrating a data table for a translation error compensation amount and a rotation error compensation amount;

FIG. 6 is a block diagram illustrating an embodiment of a translation/rotation error compensation amount creating device according to the present invention which inputs a translation error compensation amount and a rotation error compensation amount both depending on rotation axes to a numerical controller;

FIG. 7 is a block diagram illustrating another embodiment of the translation/rotation error compensation amount creating device according to the present invention included in the numerical controller;

FIG. 8 is a flowchart showing a flow of processing carried out by a translation error compensation amount calculating section and a translation error compensation amount input section in a first embodiment of the translation/rotation error compensation amount creating device according to the present invention;

FIG. 9 is a block diagram illustrating an embodiment of the translation/rotation error compensation amount creating device according to the present invention which obtains the

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positions of two rotation axes from the numerical controller and which calculates the translation error compensation amount and rotation error compensation amount depending on the rotation axes and input the calculated results to the numerical controller;

FIG. 10 is a diagram illustrating a tool head rotating multi-axis machining apparatus (5-axis machining apparatus) without any assembly error;

FIG. 11 is a diagram illustrating that, when $A=0$, a direction of a tool head is a Z axis direction in the tool head rotating multi-axis machining apparatus (5-axis machining apparatus) shown in FIG. 10;

FIG. 12 is a diagram illustrating that an assembly error including an assembly error in a spindle turning centerline is represented as an error in the rotation axis rotation centerline and an error in the spindle turning centerline (translation error and rotation error);

FIG. 13 is a diagram showing how the displaced rotation axis rotation centerline varies, focusing only on the rotation axis rotation centerline;

FIG. 14 is a diagram illustrating a mixed multi-axis machining apparatus (5-axis machining apparatus) to which the translation/rotation error compensation amount creating device according to the present invention is applied; and

FIG. 15 is a diagram illustrating one-dimensional data tables for a C axis and an A axis, respectively.

DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENTS

First Embodiment

<1> Target Machine and Errors

FIG. 1 shows a table rotating multi-axis machining apparatus (5-axis machining apparatus) without any assembly error. In this case, a table 2 rotates with respect to an A axis and a C axis, and a tool head 4 equipped with a tool 6 with a tool center point 8 moves with respect to an X axis, a Y axis, and a Z axis. Another axial configuration may be used if the machining apparatus includes a table 2 that rotates with respect to two rotation axes.

When $A=0$, the rotary table is horizontally placed as shown in FIG. 1. An original A axis rotation centerline Ca_{-T} is orthogonal to an original C axis rotation centerline Cc_{-T} , and the original C axis rotation centerline Cc_{-T} coincides with an original table centerline Ct_{-T} . In this case, "C" means "Correct", and "A" in A_{-T} described below (displaced table centerline) and the like means "Actual". Furthermore, " $-T$ " means that the data forms an error in the table. A position instruction for the A axis and the C axis, which are rotation axes, is denoted by (a, c).

As shown in FIG. 2, an assembly error including an assembly error in the table surface is represented as an error in a rotation axis rotation centerline (A axis rotation centerline and C axis rotation centerline) and an assembly error (translation error and rotation error) in the table surface with respect to the table centerline (C axis rotation centerline). Errors are exaggerated in FIG. 2, though the actual errors are small.

Errors are represented as follows. The errors are pre-measured and set by an assembly error setting section.

1) An Error in a Displaced Table Centerline At_{-T} with Respect to the Original Table Centerline Ct_{-T}

$\delta t_{-T} (\delta tx_{-T}, \delta ty_{-T}, \delta tz_{-T})^T$: an X component, a Y component, and a Z component of a deviation distance from Ct_{-T} observed when $A=0$ and $C=0$ and corresponding to Co_{-T} that

is an intersecting point between the original A axis rotation centerline and the original C axis rotation centerline, to At_{-T} . This is a translation error in the assembly error in the table surface. “T” represents transposition but will not particularly be described when the transposition is obvious.

($\alpha_{t_{-T}}$, $\beta_{t_{-T}}$, $\gamma_{t_{-T}}$): this indicates that, when $A=0$ and $C=0$, At_{-T} is tilted from Ct_{-T} with a rotation error $\alpha_{t_{-T}}$ around an X axis, a rotation error $\beta_{t_{-T}}$ around a Y axis, and a rotation error $\gamma_{t_{-T}}$ around a Z axis. This is a rotation error in the assembly error in the table surface and is expressed in radian. Data indicative of an angle is hereinafter expressed in radian unless otherwise specified.

$n_{t_{-T}}$: a direction vector of At_{-T} . Thus, $n_{t_{-T}}$ is normal to the actual (displaced) table surface.

2) An Error in the Displaced C Axis Rotation Centerline Ac_{-T} with Respect to the Original C Axis Rotation Centerline Cc_{-T}

δc_{-T} ($\delta c_{x_{-T}}$, $\delta c_{y_{-T}}$, $\delta c_{z_{-T}}$): the X component, Y component, and Z component of a deviation distance from Cc_{-T} observed when $A=0$ and corresponding to Co_{-T} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline, to Ac_{-T} . This is a translation error in an assembly error in the C axis.

In this case, Ac_{-T} may vary like a top depending on the position of the C axis. Then, δc_{-T} is $\delta c_{-T}(c)$ ($\delta c_{x_{-T}}(c)$, $\delta c_{y_{-T}}(c)$, $\delta c_{z_{-T}}(c)$) varying depending on c .

Moreover, Ac_{-T} may be affected by the position of the other axis. If Ac_{-T} is affected by the position of the A axis, δc_{-T} is $\delta c_{-T}(a, c)$ ($\delta c_{x_{-T}}(a, c)$, $\delta c_{y_{-T}}(a, c)$, $\delta c_{z_{-T}}(a, c)$) varying depending on (a, c) . FIG. 3 illustrates how Ac_{-T} and Aa_{-T} , described next, vary, focusing only on the rotation axis rotation centerline.

($\alpha_{c_{-T}}$, $\beta_{c_{-T}}$, $\gamma_{c_{-T}}$): this indicates that, when $A=0$, Ac_{-T} is tilted from Cc_{-T} with a rotation error $\alpha_{c_{-T}}$ around the X axis, a rotation error $\beta_{c_{-T}}$ around the Y axis, and a rotation error $\gamma_{c_{-T}}$ around the Z axis. This is a rotation error in the assembly error in the C axis. As is the case with δc_{-T} , if Ac_{-T} varies depending on the position of the C axis, ($\alpha_{c_{-T}}$, $\beta_{c_{-T}}$, $\gamma_{c_{-T}}$) is ($\alpha_{c_{-T}}(c)$, $\beta_{c_{-T}}(c)$, $\gamma_{c_{-T}}(c)$) varying depending on c . Moreover, if Ac_{-T} is affected by the position of the other axis (A axis), ($\alpha_{c_{-T}}$, $\beta_{c_{-T}}$, $\gamma_{c_{-T}}$) is ($\alpha_{c_{-T}}(a, c)$, $\beta_{c_{-T}}(a, c)$, $\gamma_{c_{-T}}(a, c)$) varying depending on (a, c) (see FIG. 3).

$n_{c_{-T}}$: a direction vector of Ac_{-T} .

3) An Error in the Displaced A Axis Rotation Centerline Aa_{-T} with Respect to the Original A Axis Rotation Centerline Ca_{-T}

δa_{-T} ($\delta a_{x_{-T}}$, $\delta a_{y_{-T}}$, $\delta a_{z_{-T}}$): the X component, Y component, and Z component of a deviation distance from Ca_{-T} corresponding to Co_{-T} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline, to Aa_{-T} . This is a translation error in an assembly error in the A axis. As is the case with δc_{-T} , if Aa_{-T} varies depending on the position of the A axis, δa_{-T} is $\delta a_{-T}(a)$ ($\delta a_{x_{-T}}(a)$, $\delta a_{y_{-T}}(a)$, $\delta a_{z_{-T}}(a)$) varying depending on a (see FIG. 3).

($\alpha_{a_{-T}}$, $\beta_{a_{-T}}$, $\gamma_{a_{-T}}$): this indicates that Aa_{-T} is tilted from Ca_{-T} with a rotation error $\alpha_{a_{-T}}$ around the X axis, a rotation error $\beta_{a_{-T}}$ around the Y axis, and a rotation error $\gamma_{a_{-T}}$ around the Z axis. This is a rotation error in the assembly error in the A axis. As is the case with δa_{-T} , if Aa_{-T} varies depending on the position of the A

axis, ($\alpha_{a_{-T}}$, $\beta_{a_{-T}}$, $\gamma_{a_{-T}}$) is ($\alpha_{a_{-T}}(a)$, $\beta_{a_{-T}}(a)$, $\gamma_{a_{-T}}(a)$) varying depending on a (see FIG. 3).

$n_{a_{-T}}$: a direction vector of Aa_{-T} .

<2> Translation Error Compensation Amount and Rotation Error Compensation Amount Depending on the Rotation Axes

A workpiece is placed on the table. Here, an assembly error in the table (translation error δt_{-T} ($\delta t_{x_{-T}}$, $\delta t_{y_{-T}}$, $\delta t_{z_{-T}}$) and a rotation error ($\alpha_{t_{-T}}$, $\beta_{t_{-T}}$, $\gamma_{t_{-T}}$) are focused on. Then, when $A=0$ and $C=0$, a translation error compensation amount (ΔXR , ΔYR , ΔZR) and a rotation error compensation amount (ΔIR , ΔJR , ΔKR) both depending on the rotation axes (A axis and C axis) are δt_{-T} ($\delta t_{x_{-T}}$, $\delta t_{y_{-T}}$, $\delta t_{z_{-T}}$) and ($\alpha_{t_{-T}}$, $\beta_{t_{-T}}$, $\gamma_{t_{-T}}$), respectively.

Errors in the table are compensated so as to be traced, and are thus equal to compensation amounts.

When $A=a$ and $C=c$, the translation error δt_{-T} and the rotation error ($\alpha_{t_{-T}}$, $\beta_{t_{-T}}$, $\gamma_{t_{-T}}$) are varied as follows by rotation of the A axis and the C axis. When the table rotates so that $A=a$ and $C=c$, the table itself rotates around the C axis by $-c$ and around the A axis by $-a$. Thus, a translation/rotation error compensation amount calculating section 42 (see FIG. 6) carries out a calculation for a case where the table rotates around the actual C axis (displaced C axis rotation centerline, Ac_{-T}) by $-c$ and around the actual A axis (displaced A axis rotation centerline, Aa_{-T}) by $-a$. In the calculation, square terms for an error and an error compensation amount are neglected. Furthermore, when a rotation error is denoted by e , $|e| \ll 1$, and the following approximations are carried out: $\sin(e)=e$ and $\cos(e)=1$. This is also applicable to embodiments to be described later.

<2-1> Translation Error Compensation Amount

A translation error δt_{-T} ($\delta t_{x_{-T}}$, $\delta t_{y_{-T}}$, $\delta t_{z_{-T}}$) in the table is rotated around the displaced C axis rotation centerline Ac_{-T} by $-c$ and further around the displaced A axis rotation centerline Aa_{-T} by $-a$.

A matrix that rotates, by $-c$, around a vector $n_{c_{-T}}$ indicative of the direction of Ac_{-T} observed when $A=0$ is denoted by Mc_{-T} . A matrix that rotates, by $-a$, around a vector $n_{a_{-T}}$ indicative of the direction of Aa_{-T} is denoted by Ma_{-T} .

The expression “A translation error δt_{-T} ($\delta t_{x_{-T}}$, $\delta t_{y_{-T}}$, $\delta t_{z_{-T}}$) in the table is rotated around Ac_{-T} by $-c$ and further around Aa_{-T} by $-a$ ” means that δt_{-T} ($=t_{x_{-T}}$, $\delta t_{y_{-T}}$, $\delta t_{z_{-T}}$) is rotated around $n_{c_{-T}}$ in δc_{-T} by $-c$ and further around $n_{a_{-T}}$ in δa_{-T} by $-a$. Thus, the translation error compensation amount (ΔXR , ΔYR , ΔZR) corresponding to the position of the A axis (a) and the position of the C axis (c) (that is, depending on the rotation axes) is as expressed by:

$$\begin{bmatrix} \Delta XR \\ \Delta YR \\ \Delta ZR \end{bmatrix} = Ma_{-T} * \{ Mc_{-T} * (\delta t_{-T} - \delta c_{-T}) + \delta c_{-T} - \delta a_{-T} \} + \delta a_{-T} \quad (1)$$

$$= \begin{bmatrix} (\delta t_{x_{-T}} - \delta c_{x_{-T}}) \cos(c) + (\delta t_{y_{-T}} - \delta c_{y_{-T}}) \sin(c) + \delta c_{x_{-T}} \\ \{ -(\delta t_{y_{-T}} - \delta c_{y_{-T}}) \sin(c) + (\delta t_{x_{-T}} - \delta c_{x_{-T}}) \cos(c) + \\ \delta c_{y_{-T}} - \delta a_{y_{-T}} \} \cos(a) + (\delta t_{z_{-T}} - \delta a_{z_{-T}}) \sin(a) + \delta a_{y_{-T}} \\ \{ -(\delta t_{y_{-T}} - \delta c_{y_{-T}}) \sin(c) + (\delta t_{x_{-T}} - \delta c_{x_{-T}}) \cos(c) + \\ \delta c_{y_{-T}} - \delta a_{y_{-T}} \} \sin(a) + (\delta t_{z_{-T}} - \delta a_{z_{-T}}) \cos(a) + \delta a_{z_{-T}} \end{bmatrix}$$

<2-2> Rotation Error Compensation Amount

A rotation error ($\alpha_{t_{-T}}$, $\beta_{t_{-T}}$, $\gamma_{t_{-T}}$) in the table rotates around the C axis rotation centerline Ac_{-T} by $-c$ and further around the A axis rotation centerline Aa_{-T} by $-a$. A vector in

the correct table centerline direction observed when A=a and C=c is denoted by n_{Z-T} . A rotation matrix M_I based on the rotation error compensation amount (ΔIR , ΔJR , ΔKR) corresponding to the position of the vector when A=a and C=c (that is, the rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on the rotation axes), is expressed by:

$$M_I = \begin{bmatrix} 1 & -\Delta KR & \Delta JR \\ \Delta KR & 1 & -\Delta JR \\ -\Delta JR & \Delta IR & 1 \end{bmatrix} \quad (2)$$

A direction obtained from compensation of the vector n_{Z-T} using the rotation error compensation amount (ΔIR , ΔJR , ΔKR) corresponds to a direction resulting from rotation of the vector n_{Z-T} around A_{c-T} by -c and further around A_{a-T} by -a, and thus, Formula (3) holds true.

$$\begin{bmatrix} \beta_{L-T} \cos(c) - \alpha_{L-T} \sin(c) + \beta_{c-T}(1 - \cos(c)) + \alpha_{c-T} \sin(c) - \\ \beta_{a-T}(1 - \cos(a)) - \gamma_{a-T} \sin(a) \\ \{-\beta_{L-T} \sin(c) - \alpha_{L-T} \cos(c) - \alpha_{c-T}(1 - \cos(c)) + \\ \beta_{c-T} \sin(c)\} \cos(a) + \sin(a) \\ -\{-\beta_{L-T} \sin(c) - \alpha_{L-T} \cos(c) - \alpha_{c-T}(1 - \cos(c)) + \\ \beta_{c-T} \sin(c)\} \sin(a) + \cos(a) \end{bmatrix} = \begin{bmatrix} -\Delta KR \sin(a) + \Delta JR \cos(a) \\ \sin(a) - \Delta IR \cos(a) \\ \Delta IR \sin(a) + \cos(a) \end{bmatrix} \quad (3)$$

Formula (4) is obtained from the second and third elements of Formula (3).

$$\Delta IR = -\{-\beta_{L-T} \sin(c) - \alpha_{L-T} \cos(c) - \alpha_{c-T}(1 - \cos(c)) + \beta_{c-T} \sin(c)\} \quad (4)$$

ΔJR and ΔKR are determined from the first element of Formula (3) but are not uniquely determined. Thus, on the assumption that a denotes a tilting axis and is movable within the range of about -85 degrees <a<85 degrees ($\cos(a)$ does not assume a value close to 0), $0.0871 < \cos(a) \leq 1$. Thus, ΔJR and ΔKR are determined as shown in Formula (5). The rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on the rotation axes is determined as described above. Of course, another solution meets Formula (3).

$$\Delta KR = \gamma_{a-T} \quad (5)$$

$$\Delta JR = \frac{\beta_{L-T} \cos(c) - \alpha_{L-T} \sin(c) + \beta_{c-T}(1 - \cos(c)) + \alpha_{c-T} \sin(c) - \beta_{a-T}(1 - \cos(a))}{\cos(a)}$$

Now, it is assumed that a workpiece is installed on the displaced table as shown in FIG. 4. More specifically, as shown in FIG. 4, it is assumed that a workpiece 10 is installed on a displaced workpiece installation surface 12 on the displaced table in FIG. 2 (the displaced workpiece 10 is placed on the displaced workpiece installation surface 12). In this case, like “1) An error in the displaced table centerline A_{t-T} with respect to the original table centerline C_{t-T} ” in “<1> Target machine and errors”, the following error is present.

4) An Error in a Displaced Workpiece Centerline A_{w-T} with Respect to the Original Workpiece Centerline C_{w-T} :

δw_{-T} (δw_{x-T} , δw_{y-T} , δw_{z-T}): the X component, Y component, and Z component of a deviation distance from C_{w-T} observed when A=0 and C=0 and corresponding to C_{o-T} that is an intersecting point between the original A axis rotation centerline and the original C axis rotation centerline, to A_{w-T} . This is a translation error in an installation assembly error during workpiece installation.

(α_{w-T} , β_{w-T} , γ_{w-T}): this indicates that, when A=0 and C=0, A_{w-T} is tilted from C_{w-T} with a rotation error α_{w-T} around the X axis, a rotation error β_{w-T} around the Y axis, and a rotation error γ_{w-T} around the Z axis. This is a rotation error in the installation error during workpiece installation.

n_{w-T} : a direction vector of A_{w-T} . Thus, n_{w-T} is normal to the actual (displaced) workpiece installation surface.

In this case, when the processing described in “<2-1> Translation error compensation amount” and “<2-2> Rotation error compensation amount” is carried out using “4) An error in a displaced workpiece centerline A_{w-T} with respect to the original workpiece centerline C_{w-T} ” instead of “1) An error in the displaced table centerline A_{t-T} with respect to the original table centerline C_{t-T} ”, the installation error (translation error and rotation error) during work installation may also be considered to be an assembly error (translation error and rotation error) in the table surface as described above. Obviously, a resultant error of the assembly error (translation error and rotation error) in the table surface and the installation error (translation error and rotation error) during work installation may also be considered to be an assembly error (translation error and rotation error) in the table surface. Thus, the assembly error in the table surface according to the present invention includes the installation error (translation error and rotation error) during workpiece installation.

<3> Input of the Translation Error Compensation Amount and the Rotation Error Compensation Amount

<3-1> Input to a Translation Error Compensation Amount and Rotation Error Compensation Amount Data Table in the Numerical Controller

As disclosed in JP 2009-151756 A, some numerical controllers contain a translation error compensation amount and rotation error compensation amount data table. The translation error compensation amount and rotation error compensation amount depending on the rotation axes calculated according to the present invention are input to such a numerical controller and set in the data table in the numerical controller.

The data table is configured like a grid as shown in FIG. 5. The translation error compensation amount (VnX , VnY , VnZ) and the rotation error compensation amount (VnI , VnJ , VnK) corresponding to each grid point (ai , cj) ($i=1, 2, \dots, j=1, 2, \dots$) are input to and set in the numerical controller.

In this case, (ai , cj) denotes the positions of the A axis and the C axis pre-specified in the numerical controller and corresponding to each grid point, and n denotes a grid point number corresponding to a combination (i, j). Thus, the translation error compensation amount (ΔXR , ΔYR , ΔZR) and rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on the rotation axes (A axis and C axis) corresponding to each grid point (ai , cj) are determined, and the resultant translation error compensation amount (VnX , VnY , VnZ) and rotation error compensation amount (VnI , VnJ , VnK) are input to and set in the numerical controller. That

is, with (a, c)=(ai, cj) set, the processing described in “<2-1> Translation error compensation amount” and “<2-2> Rotation error compensation amount” is carried out to determine (ΔXR , ΔYR , ΔZR) and (ΔIR , ΔJR , ΔKR). Then, the resultant translation error compensation amount (VnX , VnY , VnZ) and rotation error compensation amount (VnI , VnJ , VnK) corresponding to (ai, cj) are input to and set in the numerical controller in accordance with:

$$\begin{aligned} VnX &= \Delta XR, VnY = \Delta YR, VnZ = \Delta ZR \\ VnI &= \Delta IR, VnJ = \Delta JR, VnK = \Delta KR. \end{aligned} \quad (6)$$

In this case, a block diagram in FIG. 6 shows a first embodiment of a translation/rotation error compensation amount creating device according to the present invention which inputs the translation error compensation amount (ΔXR , ΔYR , ΔZR) and rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on the rotation axes to the numerical controller. That is, a numerical controller 30 analyzes an input machining program 20 by an instruction analyzing section 31 and carries out interpolation by an interpolation section 32 based on the analysis data. The interpolation section 32 further carries out compensation based on a translation error compensation amount and rotation error compensation amount data table 33 and the current position to drive respective axis servos 34X, 34Y, 34Z, 34A, and 34C. Thus, the numerical controller 30 controls a multi-axis machining apparatus having at least two rotation axes. The instruction analyzing section 31 and interpolation section 32 of the numerical controller 30 are collectively referred to as a numerical control section.

The compensation is performed by the interpolation section 32, but the compensation method carried out by the interpolation section 32 is a conventional technique also described in JP 2009-151756 A and will thus not particularly be described. An assembly error 43 including at least an assembly error in a table surface or an assembly error in a spindle turning centerline is set in the translation/rotation error compensation amount creating device 40 by an assembly error setting section 44. The translation/rotation error compensation amount calculating section 42 calculate the assembly error 43 and the translation error compensation amount (ΔXR , ΔYR , ΔZR) and rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on the rotation axes and corresponding to positions of two rotation axes (ai, cj), by setting (a, c)=(ai, cj) in the above-described processing. A translation/rotation error compensation amount input section 41 inputs these translation error compensation amount and the rotation error compensation amount to the numerical controller 30.

Furthermore, the translation/rotation error compensation amount creating device 40 may be incorporated in the numerical controller 30 as shown in FIG. 7.

<3-2> Direct Input of the Translation Error Compensation Amount and the Rotation Error Compensation Amount to the Numerical Controller

JP 2009-151756 A discloses a numerical controller that performs compensation based on the translation error compensation amount and the rotation error compensation amount. The positions (a, c) of the two rotation axes are obtained from the numerical controller, and the translation error compensation amount (ΔXR , ΔYR , ΔZR) and rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on

the rotation axes, calculated according to the present invention, are input to a numerical controller 50, which then performs compensation.

In this case, a block diagram in FIG. 9 shows the first embodiment of the translation/rotation error compensation amount creating device according to the present invention which obtains the positions (a, c) of the two rotation axes and which calculates the translation error compensation amount (ΔXR , ΔYR , ΔZR) and rotation error compensation amount (ΔIR , ΔJR , ΔKR) both depending on the rotation axes and inputs the calculated result to the numerical controller. That is, a numerical controller 50 analyzes an input machining program 20 by an instruction analyzing section 51 and carries out interpolation by an interpolation section 52 based on the analysis data. The interpolation section 52 further carries out compensation based on the translation error compensation amount, the rotation error compensation amount, and the current position to drive the respective axis servos 34X, 34Y, 34Z, 34A, and 34C. The compensation method to be carried out by the interpolation section 52 is a conventional technique as described in JP 2009-151756 A mentioned above and will thus not particularly be described.

In this case, the assembly error 43 including at least the assembly error in the table surface or the assembly error in the spindle turning centerline is set in the translation/rotation error compensation amount creating device 40 by the assembly error setting section 44. The positions (a, c) of the two rotation axes are obtained from the numerical controller 50 at every interpolation period. The translation/rotation error compensation amount calculating section 42 calculates the assembly error 43 and the translation error compensation amount (ΔXR , ΔYR , ΔZR) and rotation error compensation amount (ΔIR , ΔJR , ΔKR) both depending on the rotation axes and corresponding to the positions (a, c) of the two rotation axes. The translation/rotation error compensation amount input section 41 inputs these translation error compensation amount and the rotation error compensation amount to the numerical controller 50.

Furthermore, the translation/rotation error compensation amount creating device 40 may be incorporated in the numerical controller 50 as is the case with FIG. 7.

With reference to a flowchart in FIG. 8, a flow of processing will be described which is carried out by the translation/rotation error compensation amount calculating section 42 and translation/rotation error compensation amount input section 41 in the first embodiment of the translation/rotation error compensation amount creating device according to the present invention. The flow of the processing will be described in accordance with steps of the flowchart.

[Step SA01] The translation/rotation error compensation amount calculating section 42 sets a=ai and c=cj for the positions (ai, cj) of the A axis and the C axis corresponding to each grid point and pre-specified in the numerical controller 30.

[Step SA02] In accordance with Formula (1), the translation/rotation error compensation amount calculating section 42 calculates the translation error compensation amount (ΔXR , ΔYR , ΔZR) depending on the rotation axes and corresponding to the positions (a, c) of the A axis and the C axis.

[Step SA03] In accordance with Formulae (2) to (5), the translation/rotation error compensation amount calculating section 42 calculates the rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on the rotation axes and corresponding to the positions (a, c) of the A axis and the C axis.

[Step SA04] In accordance with Formula (6), the translation/rotation error compensation amount input section 41 calcu-

lates and inputs the translation error compensation amount (VnX , VnY , VnZ) and rotation error compensation amount (VnI , VnJ , VnK) corresponding to (ai, cj), and inputs the calculated results to the numerical controller 30, and the process is ended.

Second Embodiment

<1> Target Machine and Errors

FIG. 10 shows a tool head rotating multi-axis machining apparatus (5-axis machining apparatus) without any assembly error. In this case, a tool head moves with respect to the X axis, the Y axis, and the Z axis, and rotates with respect to the A axis and the C axis. Another axial configuration may be used if the machining apparatus includes a tool head that rotates with respect to two rotation axes.

When $A=0$, a tool direction of the tool head is a Z axis direction as shown in FIG. 11. An original A axis rotation centerline Ca_{-H} is orthogonal to an original C axis rotation centerline Cc_{-H} , and the original C axis rotation centerline Cc_{-H} coincides with an original spindle turning centerline Cs_{-H} . In this case, “ $-H$ ” means the data that forms an error in the tool head. A position instruction for the A axis and the C axis is denoted by (a, c).

As shown in FIG. 12, an assembly error including an assembly error in the spindle turning centerline is represented as an error in the rotation axis rotation centerline (A axis rotation centerline and C axis rotation centerline) and an error in the spindle turning centerline (translation error and rotation error). Errors are exaggerated in FIG. 12, though the actual errors are small. In FIG. 12, δc_{-H} and $(\alpha c_{-H}, \beta c_{-H}, \gamma c_{-H})$ are originally separate vectors but are simplified and shown by one vector due to the lack of space.

Errors are represented as follows. The errors are pre-measured and set by an assembly error setting section.

1) An Error in a Displaced Spindle Turning Centerline As_{-H} With Respect to the Original Spindle Turning Centerline Cs_{-H}

δs_{-H} (δs_{x-H} , δs_{y-H} , δs_{z-H}): the X component, Y component, and Z component of a deviation distance from Cs_{-H} observed when $A=0$ and $C=0$ and corresponding to Co_{-H} that is an intersecting point between the original A axis rotation centerline and the original C axis rotation centerline, to As_{-H} . This is a translation error in the assembly error in the spindle turning centerline.

$(\alpha s_{-H}, \beta s_{-H}, \gamma s_{-H})$: this indicates that, when $A=0$ and $C=0$, As_{-H} is tilted from Cs_{-H} with a rotation error αs_{-H} around the X axis, the rotation error βs_{-H} around the Y axis, and a rotation error γs_{-H} around the Z axis. This is a rotation error in the assembly error in the spindle turning centerline.

n_{s-H} : a direction vector of As_{-H} . Thus, n_{s-H} is normal to the actual (displaced) spindle turning centerline direction.

2) An Error in the Displaced C Axis Rotation Centerline Ac_{-H} WITH Respect to the Original C Axis Rotation Centerline Cc_{-H}

δc_{-H} (δc_{x-H} , δc_{y-H} , δc_{z-H}): the X component, Y component, and Z component of a deviation distance from Cc_{-H} observed when $A=0$ and corresponding to Co_{-H} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline, to Ac_{-H} . This is a translation error in an assembly error in the C axis. As is the case with the first embodiment, Ac_{-H} may vary like a top depending on the position of the C axis. Then, δc_{-H} is $\delta c_{-H}(c)$

($\delta c_{x-H}(c)$, $\delta c_{y-H}(c)$, $\delta c_{z-H}(c)$) varying depending on c. FIG. 13 illustrates how Ac_{-H} and As_{-H} , described next, varies, focusing only on the rotation axis rotation centerline.

$(\alpha c_{-H}, \beta c_{-H}, \gamma c_{-H})$: this indicates that, when $A=0$, Ac_{-H} is tilted from Cc_{-H} with a rotation error αc_{-H} around the X axis, a rotation error βc_{-H} around the Y axis, and a rotation error γc_{-H} around the Z axis. This is a rotation error in the assembly error in the C axis. As is the case with δc_{-H} , if Ac_{-H} varies depending on the position of the C axis, $(\alpha c_{-H}, \beta c_{-H}, \gamma c_{-H})$ is $(\alpha c_{-H}(c), \beta c_{-H}(c), \gamma c_{-H}(c))$ varying depending on c (see FIG. 13).

n_{c-H} : a direction vector of Ac_{-H} .

3) An Error in the Displaced A Axis Rotation Centerline Aa_{-H} With Respect to the Original A Axis Rotation Centerline Ca_{-H}

δa_{-H} (δa_{x-H} , δa_{y-H} , δa_{z-H}): the X component, Y component, and Z component of a deviation distance from Ca_{-H} corresponding to Co_{-H} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline, to Aa_{-H} . This is a translation error in an assembly error in the A axis. As is the case with δc_{-H} , if Aa_{-H} varies depending on the position of the A axis, δa_{-H} is $\delta a_{-H}(a)$ ($\delta a_{x-H}(a)$, $\delta a_{y-H}(a)$, $\delta a_{z-H}(a)$) varying depending on a. Moreover, Aa_{-H} may be affected by the position of the other axis. If As_{-H} is affected by the position of the C axis, δa_{-H} is $\delta a_{-H}(a, c)$ ($\delta a_{x-H}(a, c)$, $\delta a_{y-H}(a, c)$, $\delta a_{z-H}(a, c)$) varying depending on (a, c) (see FIG. 13).

$(\alpha a_{-H}, \beta a_{-H}, \gamma a_{-H})$: this indicates that Aa_{-H} is tilted from Ca_{-H} with a rotation error αa_{-H} around the X axis, a rotation error βa_{-H} around the Y axis, and a rotation error γa_{-H} around the Z axis. This is a rotation error in the assembly error in the A axis. As is the case with δa_{-H} , if Aa_{-H} varies depending on the position of the A axis, $(\alpha a_{-H}, \beta a_{-H}, \gamma a_{-H})$ is $(\alpha a_{-H}(a), \beta a_{-H}(a), \gamma a_{-H}(a))$ varying depending on a. If Aa_{-H} is affected by the other axis (C axis) position, $(\alpha a_{-H}, \beta a_{-H}, \gamma a_{-H})$ is $(\alpha a_{-H}(a, c), \beta a_{-H}(a, c), \gamma a_{-H}(a, c))$ varying depending on (a, c) (see FIG. 13).

n_{a-H} : a direction vector of Aa_{-H} .

<2> Translation Error Compensation Amount and Rotation Error Compensation Amount Depending on the Rotation Axes

An assembly error in the spindle turning centerline (translation error δs_{-H} (δs_{x-H} , δs_{y-H} , δs_{z-H}) and a rotation error $(\alpha s_{-H}, \beta s_{-H}, \gamma s_{-H})$ are focused on. Then, when $A=0$ and $C=0$, a translation error compensation amount (ΔXR , ΔYR , ΔZR) and a rotation error compensation amount (ΔIR , ΔJR , ΔKR) both depending on the rotation axes (A axis and C axis) are $-\delta s_{-H}$ ($-\delta s_{x-H}$, $-\delta s_{y-H}$, $-\delta s_{z-H}$) and $(-\alpha s_{-H}, -\beta s_{-H}, -\gamma s_{-H})$, respectively.

Errors in the tool head are compensated so as to be retracted, and thus, the compensation amount is equal to the error in the tool head the sign of which is inverted. When $A=a$ and $C=c$, δs_{-H} and $(\alpha s_{-H}, \beta s_{-H}, \gamma s_{-H})$ are varied as follows by rotation of the A axis and the C axis.

When the tool head rotates so that $A=a$ and $C=c$, a translation/rotation error compensation amount calculating section 42 (see FIG. 9) carries out a calculation for a case where the tool head rotates around the actual A axis (displaced A axis, Aa_{-H}) by a and around the actual C axis (displaced C axis, Ac_{-H}) by c.

<2-1> Translation Error Compensation Amount

A translation error δs_{-H} (δs_{x-H} , δs_{y-H} , δs_{z-H}) in the spindle turning centerline is rotated around the displaced A axis rotation centerline Aa_{-H} by a and further around the displaced C axis rotation centerline Ac_{-H} by c .

A matrix that rotates, by a , around a vector n_{A-H} indicative of the direction of Aa_{-H} is denoted by Ma_{-H} .

A matrix that rotates, by c , around a vector n_{C-H} indicative of the direction of Ac_{-H} when $A=0$ is denoted by Mc_{-H} . The expression "A translation error δs_{-H} (δs_{x-H} , δs_{y-H} , δs_{z-H}) in the spindle turning centerline is rotated around the displaced A axis rotation centerline Aa_{-H} by a and further around the displaced C axis rotation centerline Ac_{-H} by c " means that δs_{-H} (δs_{x-H} , δs_{y-H} , δs_{z-H}) is rotated around n_{A-H} in δa_{-H} by a and further around n_{C-H} in δc_{-H} by c . Moreover, the translation error compensation amount is a sign inverted value of the translation error. Thus, the translation error compensation amount (ΔXR , ΔYR , ΔZR) corresponding to the position of the A axis (a) and the position of the C axis (c) (that is, depending on the rotation axes) are as expressed by:

$$\begin{bmatrix} \Delta XR \\ \Delta YR \\ \Delta ZR \end{bmatrix} = -Mc_{-H} * \{Ma_{-H} * (\delta s_{-H} - \delta a_{-H}) + \delta a_{-H} - \delta c_{-H}\} - \delta c_{-H} \quad (7)$$

$$= \begin{bmatrix} -(\delta s_{x-H} - \delta c_{x-H})\cos(c) + \{(\delta s_{y-H} - \delta a_{y-H})\cos(a) - (\delta s_{z-H} - \delta a_{z-H})\sin(a) + (\delta a_{y-H} - \delta c_{y-H})\} \sin(c) - \delta c_{x-H} \\ -(\delta s_{x-H} - \delta c_{x-H})\sin(c) + \{-(\delta s_{y-H} - \delta a_{y-H})\cos(a) + (\delta s_{z-H} - \delta a_{z-H})\sin(a) - (\delta a_{y-H} - \delta c_{y-H})\cos(c) - \delta c_{y-H} \\ -(\delta s_{y-H} - \delta a_{y-H})\sin(a) - (\delta s_{z-H} - \delta a_{z-H})\cos(a) - \delta a_{z-H} \end{bmatrix}$$

<2-2> Rotation Error Compensation Amount

$(\alpha s_{-H}, \beta s_{-H}, \gamma s_{-H})$ rotates around the displaced A axis rotation centerline Aa_{-H} by a and further around the displaced C axis rotation centerline Ac_{-H} by c . A vector obtained in the correct spindle turning centerline direction when $A=a$ and $C=c$ is denoted by n_{Z-H} . When $A=a$ and $C=c$, a rotation matrix M_I based on the rotation error compensation amount (ΔIR , ΔJR , ΔKR) corresponding to the position of the vector (that is, depending on the rotation axes) is, as with the case with the first embodiment, expressed by:

$$M_I = \begin{bmatrix} 1 & -\Delta KR & \Delta JR \\ \Delta KR & 1 & -\Delta IR \\ -\Delta JR & \Delta IR & 1 \end{bmatrix} \quad (8)$$

The vector n_{Z-H} corresponds to a direction obtained by compensation, using the rotation error compensation amount (ΔIR , ΔJR , ΔKR), of a direction resulting from rotation of the direction vector n_{S-H} around the A axis rotation centerline Aa_{-H} by a and further around the C axis rotation centerline Ac_{-H} by c . Thus, Formula (9) holds true.

$$\begin{bmatrix} \{\beta s_{-H} - \beta a_{-H}(1 - \cos(a)) + \gamma a_{-H}\sin(a)\}\cos(c) + \{\alpha s_{-H}\cos(a) + \sin(a)\}\sin(c) + \{\beta c_{-H}(1 - \cos(c)) - \alpha c_{-H}\sin(c)\}\cos(a) \\ \{\beta s_{-H} - \beta a_{-H}(1 - \cos(a)) + \gamma a_{-H}\sin(a)\}\sin(c) - \{\alpha s_{-H}\cos(a) + \sin(a)\}\cos(c) + \{-\alpha c_{-H}(1 - \cos(c)) - \beta c_{-H}\sin(c)\}\cos(a) \\ -\{-\alpha c_{-H}(1 - \cos(c)) + \beta c_{-H}\sin(c)\}\sin(a) - \alpha s_{-H}\sin(a) + \cos(a) \end{bmatrix} = \quad (9)$$

$$\begin{bmatrix} \sin(c)\sin(a) - \Delta KR\cos(c)\sin(a) - \Delta JR\cos(a) \\ -\Delta KR\sin(c)\sin(a) - \cos(c)\sin(a) + \Delta IR\cos(a) \\ \Delta JR\sin(c)\sin(a) + \Delta IR\cos(c)\sin(a) + \cos(a) \end{bmatrix}$$

Given -85 degrees $< a < 85$ degrees as is the case with the first embodiment, Formula (10) is obtained from Formula (9). The rotation error compensation amount (ΔIR , ΔJR , ΔKR) depending on the rotation axes is determined as described above. Of course, another solution meets Formula (9).

$$\Delta IR = \beta a_{-H}\sin(c) - \alpha s_{-H}\cos(c) - \quad (10)$$

$$\alpha c_{-H}(1 - \cos(c)) - \beta c_{-H}\sin(c) + \frac{(\beta s_{-H} - \beta a_{-H})\sin(c)}{\cos(a)}$$

$$\Delta JR = -\beta a_{-H}\cos(c) - \alpha s_{-H}\sin(c) + \alpha c_{-H}\sin(c) -$$

$$\beta c_{-H}(1 - \cos(c)) - \frac{(\beta s_{-H} - \beta a_{-H})\cos(c)}{\cos(a)}$$

$$\Delta KR = -\gamma a_{-H}$$

<3> Input of the Translation Error Compensation Amount and the Rotation Error Compensation Amount

This aspect is the same as the corresponding aspect of the first embodiment and will not be described below.

Third Embodiment

<1> Target Machine and Errors

FIG. 14 shows a mixed multi-axis machining apparatus (5-axis machining apparatus) to which the translation/rotation error compensation amount creating device according to the present invention is applied. In this case, a tool head moves with respect to the X axis, the Y axis, and the Z axis, and rotates with respect to the A axis, and a table rotates with respect to the C axis. Another axial configuration may be used if the machining apparatus includes a tool head that rotates with respect to one of the rotation axes and a table that rotates with respect to the other rotation axis.

The present embodiment is the same as the second embodiment except that the tool head rotates with respect to one rotation axis instead of two rotation axes, and also the same as the first embodiment except that the table rotates with respect to one axis rather than two axes. Thus, the description of the third embodiment is simplified.

In FIG. 14, for example, δa_{-H} and $(\alpha a_{-H}, \beta a_{-H}, \gamma a_{-H})$, like δc_{-H} and $(\alpha c_{-H}, \beta c_{-H}, \gamma c_{-H})$ in FIG. 12, are originally separate vectors but are simplified and shown by one vector due to the lack of space.

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<2> Translation Error Compensation Amount and
Rotation Error Compensation Amount Depending
on the Rotation Axes

The calculation for only the C axis according to the first embodiment is carried out. That is, with $a=0$, $\alpha a_{-T}=0$, $\beta a_{-T}=0$, $\gamma a_{-T}=0$, $\delta a_{-T}=0$, $\delta a_{y_{-T}}=0$, and $\delta a_{z_{-T}}=0$ set, a translation error compensation amount (ΔXC , ΔYC , ΔZC) and a rotation error compensation amount (ΔIC , ΔJC , ΔKC) both depending on the rotation axis (C axis) according to the first embodiment are determined.

The calculation for only the A axis according to the second embodiment is carried out. That is, with $c=0$, $\alpha c_{-H}=0$, $\beta c_{-H}=0$, $\gamma c_{-H}=0$, $\delta c_{x_{-H}}=0$, $\delta c_{y_{-H}}=0$, and $\delta c_{z_{-H}}=0$ set, a translation error compensation amount (ΔXA , ΔYA , ΔZA) and a rotation error compensation amount (ΔIA , ΔJA , ΔKA) both depending on the rotation axis (A axis) according to the second embodiment are determined.

<3> Input of the Translation Error Compensation
Amount and the Rotation Error Compensation
Amount

<3-1> Input to a Translation Error Compensation Amount and
Rotation Error Compensation Amount Data Table in the
Numerical Controller

According to the conventional art, such a one-dimensional data table as shown in FIG. 15 is provided for each of the C axis and the A axis. A translation error compensation amount (ViX , ViY , ViZ) and a rotation error compensation amount (ViI , ViJ , ViK) both corresponding to each grid point (ai) ($i=1, 2, \dots$) are input to and set in the data tables.

Thus, the translation error compensation amount (ΔXA , ΔYA , ΔZA) and rotation error compensation amount (ΔIA , ΔJA , ΔKA) both depending on the A axis and corresponding to each grid point (ai) are determined, and are input to and set in the numerical controller as the translation error compensation amount (ViX , ViY , ViZ) and the rotation error compensation amount (ViI , ViJ , ViK). That is, the translation/rotation error compensation amount creating device sets a equal to ai ($a=ai$) and determines the translation error compensation amount (ΔXA , ΔYA , ΔZA) and rotation error compensation amount (ΔIA , ΔJA , ΔKA) both depending on the rotation axis (A axis). The translation/rotation error compensation amount creating device then inputs and sets the determined (ΔXA , ΔYA , ΔZA) and (ΔIA , ΔJA , ΔKA) as translation error compensation amount (ViX , ViY , ViZ) and rotation error compensation amount (ViI , ViJ , ViK) corresponding to (ai) in the numerical controller in accordance with:

$$ViX = \Delta XA, ViY = \Delta YA, ViZ = \Delta ZA \quad (11)$$

$$ViI = \Delta IA, ViJ = \Delta JA, ViK = \Delta KA.$$

The translation/rotation error compensation amount creating device is also configured to input and set a translation error compensation amount (VjX , VjY , VjZ) and a rotation error compensation amount (VjI , VjJ , VjK) both corresponding to each grid point (cj) ($j=1, 2, \dots$) in the numerical controller. Thus, the translation/rotation error compensation amount creating device similarly determines the translation error compensation amount (ΔXC , ΔYC , ΔZC) and rotation error compensation amount (ΔIC , ΔJC , ΔKC) depending on the rotation axis (C axis) and corresponding to each grid

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point (cj). The translation/rotation error compensation amount creating device then inputs and sets the determined (ΔXC , ΔYC , ΔZC) and (ΔIC , ΔJC , ΔKC) as translation error compensation amount (VjX , VjY , VjZ) and rotation error compensation amount (VjI , VjJ , VjK) in the numerical controller.

In this case, a block diagram in FIG. 6 or FIG. 7 shows a third embodiment of the translation/rotation error compensation amount creating device according to the present invention which inputs the translation error compensation amount and rotation error compensation amount depending on the rotation axis to the numerical controller.

<3-2> Direct Input of the Translation Error Compensation
Amount and the Rotation Error Compensation Amount to
the Numerical Controller

Some numerical controllers perform compensation based on the translation error compensation amount and the rotation error compensation amount as disclosed in JP 2009-151756 A. The translation/rotation error compensation amount creating device 40 obtains the positions (a, c) of the two rotation axes from such a numerical controller 50 as described above. The translation/rotation error compensation amount creating device 40 then inputs the translation error compensation amounts (ΔXA , ΔYA , ΔZA) and (ΔXC , ΔYC , ΔZC) and rotation error compensation amounts (ΔIA , ΔJA , ΔKA) and (ΔIC , ΔJC , ΔKC) determined as described above and depending on the rotation axes to the numerical controller 50. The numerical controller 50 perform compensation based on the input values. In this case, the block diagram in FIG. 9 shows the third embodiment of the translation/rotation error compensation amount creating device according to the present invention which obtains the positions (a, c) of the two rotation axes from the numerical controller and which calculates and inputs the translation error compensation amount and rotation error compensation amount depending on the rotation axes to the numerical controller. Furthermore, the translation/rotation error compensation amount creating device 40 may be incorporated in the numerical controller 50 as is the case with the first embodiment.

What is claimed is:

1. A translation/rotation error compensation amount creating device for creating, for a multi-axis machining apparatus having at least two rotation axes, a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes, the translation/rotation error compensation amount creating device comprising:

an assembly error setting section configured to preset an assembly error including at least an assembly error in a table surface or an assembly error in a spindle turning centerline in the multi-axis machining apparatus;

a translation/rotation error compensation amount calculating section configured to calculate

the translation error compensation amount by a first arithmetic expression based on the assembly error and positions of the two rotation axes, and

the rotation error compensation amount by a second arithmetic expression for solving an equation based on

a correct direction vector of the table surface or the spindle turning centerline based on the positions of the two rotation axes,

the rotation error compensation amount, the assembly error, and

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an actual direction vector of the table surface or the spindle turning centerline based on the positions of the two rotation axes; and

a translation/rotation error compensation amount input section configured to input the calculated translation error compensation amount and the rotation error compensation amount to a translation error compensation amount and rotation error compensation amount data table in a numerical controller controlling the multi-axis machining apparatus,

wherein

the multi-axis machining apparatus is a table rotating multi-axis machining apparatus having a rotary table, the translation/rotation error compensation amount creating device is configured to convert the assembly error in the table surface in the table rotating multi-axis machining apparatus into the translation error compensation amount and the rotation error compensation amount both depending on the rotation axes,

the two rotation axes include an A axis and a C axis,

the first arithmetic expression for calculating the translation error compensation amount (ΔXR , ΔYR , ΔZR) corresponding to a position (a) of the A axis and a position (c) of the C axis is as follows:

$$\begin{bmatrix} \Delta XR \\ \Delta YR \\ \Delta ZR \end{bmatrix} = Ma_{-T}^* \{ Mc_{-T}^* (\delta t_{-T} - \delta c_{-T}) + \delta c_{-T} - \delta a_{-T} \} + \delta a_{-T}$$

$$= \begin{bmatrix} (\delta t_{x-T} - \delta c_{x-T}) \cos(c) + (\delta t_{y-T} - \delta c_{y-T}) \sin(c) + \delta c_{x-T} \\ \{ -(\delta t_{y-T} - \delta c_{y-T}) \sin(c) + (\delta t_{x-T} - \delta c_{x-T}) \cos(c) + \delta c_{y-T} - \delta a_{y-T} \} \cos(a) + (\delta t_{z-T} - \delta a_{z-T}) \sin(a) + \delta a_{y-T} \\ - \{ (\delta t_{y-T} - \delta c_{y-T}) \sin(c) + (\delta t_{x-T} - \delta c_{x-T}) \cos(c) + \delta c_{y-T} - \delta a_{y-T} \} \sin(a) + (\delta t_{z-T} - \delta a_{z-T}) \cos(a) + \delta a_{z-T} \end{bmatrix},$$

and

the second arithmetic expression for calculating the rotation error compensation amount (ΔIR , ΔJR , ΔKR) is as follows:

$$\begin{bmatrix} \beta t_{-T} \cos(c) - \alpha t_{-T} \sin(c) + \beta c_{-T} (1 - \cos(c)) + \alpha c_{-T} \sin(c) - \beta a_{-T} (1 - \cos(a)) - \gamma a_{-T} \sin(a) \\ \{ -\beta t_{-T} \sin(c) - \alpha t_{-T} \cos(c) - \alpha c_{-T} (1 - \cos(c)) + \beta c_{-T} \sin(c) \} \cos(a) + \sin(a) \\ - \{ -\beta t_{-T} \sin(c) - \alpha t_{-T} \cos(c) - \alpha c_{-T} (1 - \cos(c)) + \beta c_{-T} \sin(c) \} \sin(a) + \cos(a) \end{bmatrix} =$$

$$\begin{bmatrix} -\Delta KR \sin(a) + \Delta JR \cos(a) \\ \sin(a) - \Delta IR \cos(a) \\ \Delta IR \sin(a) + \cos(a) \end{bmatrix}$$

where

an error in a displaced table centerline At_{-T} with respect to an original table centerline Ct_{-T} is as follows:

δtx_{-T} , δty_{-T} , δtz_{-T} are an X component, a Y component, and a Z component, respectively, of a deviation distance between At_{-T} and Ct_{-T} observed when $A=0$ and $C=0$ and corresponding to Co_{-T} that is an intersecting point between an original A axis rotation centerline Ca_{-T} and an original C axis rotation centerline Cc_{-T} ,

αt_{-T} , βt_{-T} , γt_{-T} indicate that, when $A=0$ and $C=0$, At_{-T} is tilted from Ct_{-T} with a rotation error αt_{-T} around

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an X axis, a rotation error βt_{-T} around a Y axis, and a rotation error γt_{-T} around a Z axis, respectively, and n_{T-T} is a direction vector of At_{-T} ,

an error in a displaced C axis rotation centerline Ac_{-T} with respect to the original C axis rotation centerline Cc_{-T} is as follows:

δcx_{-T} , δcy_{-T} , δcz_{-T} are the X component, Y component, and Z component, respectively, of a deviation distance between Ac_{-T} and Cc_{-T} observed when $A=0$ and corresponding to Co_{-T} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline,

αc_{-T} , βc_{-T} , γc_{-T} indicate that, when $A=0$, Ac_{-T} is tilted from Cc_{-T} with a rotation error αc_{-T} around the X axis, a rotation error βc_{-T} around the Y axis, and a rotation error γc_{-T} around the Z axis, respectively, and

n_{C-T} is a direction vector of Ac_{-T} ,

an error in a displaced A axis rotation centerline Aa_{-T} with respect to the original A axis rotation centerline Ca_{-T} is as follows:

δax_{-T} , δay_{-T} , δaz_{-T} are the X component, Y component, and Z component, respectively, of a deviation distance between Aa_{-T} and Ca_{-T} corresponding to Co_{-T} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline,

αa_{-T} , βa_{-T} , γa_{-T} indicate that Aa_{-T} is tilted from Ca_{-T} with a rotation error αa_{-T} around the X axis, a rotation error βa_{-T} around the Y axis, and a rotation error γa_{-T} around the Z axis, respectively, and

n_{A-T} is a direction vector of Aa_{-T} ,

Mc_{-T} is a matrix that rotates, by $-c$, around the vector n_{C-T} indicative of the direction of Ac_{-T} observed when $A=0$, and

Ma_{-T} is a matrix that rotates, by $-a$, around the vector n_{A-T} indicative of the direction of Aa_{-T} .

2. A translation/rotation error compensation amount creating device for creating, for a multi-axis machining apparatus having at least two rotation axes, a translation error compensation amount and a rotation error compensation amount both depending on the rotation axes, the translation/rotation error compensation amount creating device comprising:

an assembly error setting section configured to preset an assembly error including at least an assembly error in a table surface or an assembly error in a spindle turning centerline in the multi-axis machining apparatus;

a translation/rotation error compensation amount calculating section configured to calculate

the translation error compensation amount by a first arithmetic expression based on the assembly error and positions of the two rotation axes, and

the rotation error compensation amount by a second arithmetic expression for solving an equation based on

a correct direction vector of the table surface or the spindle turning centerline based on the positions of the two rotation axes,

the rotation error compensation amount,

the assembly error, and

an actual direction vector of the table surface or the spindle turning centerline based on the positions of the two rotation axes; and

a translation/rotation error compensation amount input section configured to input the calculated translation error compensation amount and the rotation error com-

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pensation amount to a translation error compensation amount and rotation error compensation amount data table in a numerical controller controlling the multi-axis machining apparatus,

wherein

the multi-axis machining apparatus is a tool head rotating multi-axis machining apparatus,

the translation/rotation error compensation amount creating device is configured to convert the assembly error in the spindle turning centerline in the tool head rotating multi-axis machining apparatus into the translation error compensation amount and the rotation error compensation amount both depending on the rotation axes,

the two rotation axes include an A axis and a C axis,

the first arithmetic expression for calculating the translation error compensation amount (ΔXR , ΔYR , ΔZR) corresponding to a position (a) of the A axis and a position (c) of the C axis is as follows:

$$\begin{bmatrix} \Delta XR \\ \Delta YR \\ \Delta ZR \end{bmatrix} = M c_{-H}^* \{ M a_{-H}^* (\delta s_{-H} - \delta a_{-H}) + \delta a_{-H} - \delta c_{-H} \} - \delta c_{-H}$$

$$= \begin{bmatrix} -(\delta s_{x-H} - \delta c_{x-H}) \cos(c) + \{ (\delta s_{y-H} - \delta a_{y-H}) \cos(a) - (\delta s_{z-H} - \delta a_{z-H}) \sin(a) + (\delta a_{y-H} - \delta c_{y-H}) \} \sin(c) - \delta c_{x-H} \\ -(\delta s_{x-H} - \delta c_{x-H}) \sin(c) + \{ -(\delta s_{y-H} - \delta a_{y-H}) \cos(a) + (\delta s_{z-H} - \delta a_{z-H}) \sin(a) - (\delta a_{y-H} - \delta c_{y-H}) \} \cos(c) - \delta c_{y-H} \\ -(\delta s_{y-H} - \delta a_{y-H}) \sin(a) - (\delta s_{z-H} - \delta a_{z-H}) \cos(a) + \delta a_{z-H} \end{bmatrix},$$

and

the second arithmetic expression for calculating the rotation error compensation amount (ΔIR , ΔJR , ΔKR) is as follows:

$$\begin{bmatrix} \{ \beta s_{-H} - \beta a_{-H} (1 - \cos(a)) + \gamma \alpha_{-H} \sin(a) \} \cos(c) + \{ \alpha s_{-H} \cos(a) + \sin(a) \} \sin(c) + \{ \beta c_{-H} (1 - \cos(c)) - \alpha c_{-H} \sin(c) \} \cos(a) \\ \{ \beta s_{-H} - \beta a_{-H} (1 - \cos(a)) + \gamma \alpha_{-H} \sin(a) \} \sin(c) - \{ \alpha s_{-H} \cos(a) + \sin(a) \} \cos(c) + \{ -\alpha c_{-H} (1 - \cos(c)) - \beta c_{-H} \sin(c) \} \cos(a) \\ - \{ -\alpha c_{-H} (1 - \cos(c)) + \beta c_{-H} \sin(c) \} \sin(a) - \alpha s_{-H} \sin(a) + \cos(a) \end{bmatrix} =$$

$$\begin{bmatrix} \sin(c) \sin(a) - \Delta K R \cos(c) \sin(a) - \Delta J R \cos(a) \\ -\Delta K R \sin(c) \sin(a) - \cos(c) \sin(a) + \Delta I R \cos(a) \\ \Delta J R \sin(c) \sin(a) + \Delta I R \cos(c) \sin(a) + \cos(a) \end{bmatrix},$$

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where

an error in a displaced spindle turning centerline As_{-H} with respect to an original spindle turning centerline Cs_{-H} is as follows:

δs_{x-H} , δs_{y-H} , δs_{z-H} are an X component, a Y component, and a Z component, respectively, of a deviation distance between As_{-H} and Cs_{-H} observed when $A=0$ and $C=0$ and corresponding to Co_{-H} that is an intersecting point between an original A axis rotation centerline Ca_{-H} and an original C axis rotation centerline Cc_{-H} ,

αs_{-H} , βs_{-H} , γs_{-H} indicate that, when $A=0$ and $C=0$, As_{-H} is tilted from Cs_{-H} with a rotation error αs_{-H} around an X axis, a rotation error βs_{-H} around a Y axis, and a rotation error γs_{-H} around a Z axis, respectively, and

n_{s-H} is a direction vector of As_{-H} ,

an error in a displaced C axis rotation centerline Ac_{-H} with respect to the original C axis rotation centerline Cc_{-H} is as follows:

δc_{x-H} , δc_{y-H} , δc_{z-H} are the X component, Y component, and Z component, respectively, of a deviation distance between Ac_{-H} and Cc_{-H} observed when $A=0$ and corresponding to Co_{-H} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline,

αc_{-H} , βc_{-H} , γc_{-H} indicate that, when $A=0$, Ac_{-H} is tilted from Cc_{-H} with a rotation error αc_{-H} around the X axis, a rotation error βc_{-H} around the Y axis, and a rotation error γc_{-H} around the Z axis, respectively, and

n_{c-H} is a direction vector of Ac_{-H} ,

an error in a displaced A axis rotation centerline Aa_{-H} with respect to the original A axis rotation centerline Ca_{-H} is as follows:

δa_{x-H} , δa_{y-H} , δa_{z-H} are the X component, Y component, and Z component, respectively, of a deviation distance between Aa_{-H} and Ca_{-H} corresponding to Co_{-H} that is the intersecting point between the original A axis rotation centerline and the original C axis rotation centerline,

αa_{-H} , βa_{-H} , γa_{-H} indicate that Aa_{-H} is tilted from Ca_{-H} with a rotation error αa_{-H} around the X axis, a rotation error βa_{-H} around the Y axis, and a rotation error γa_{-H} around the Z axis, respectively, and

n_{a-H} is a direction vector of Aa_{-H} ,

Ma_{-H} is a matrix that rotates, by a, around the vector n_{a-H} indicative of the direction of Aa_{-H} , and

Mc_{-H} is a matrix that rotates, by c, around the vector n_{c-H} indicative of the direction of Ac_{-H} when $A=0$.

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